

[54] TOOL STORING AND FEEDING APPARATUS

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[51] Int. Cl.⁴ B23Q 3/157

[52] U.S. Cl. 29/568; 211/1.5

[58] Field of Search 29/568, 26 A; 211/2.5

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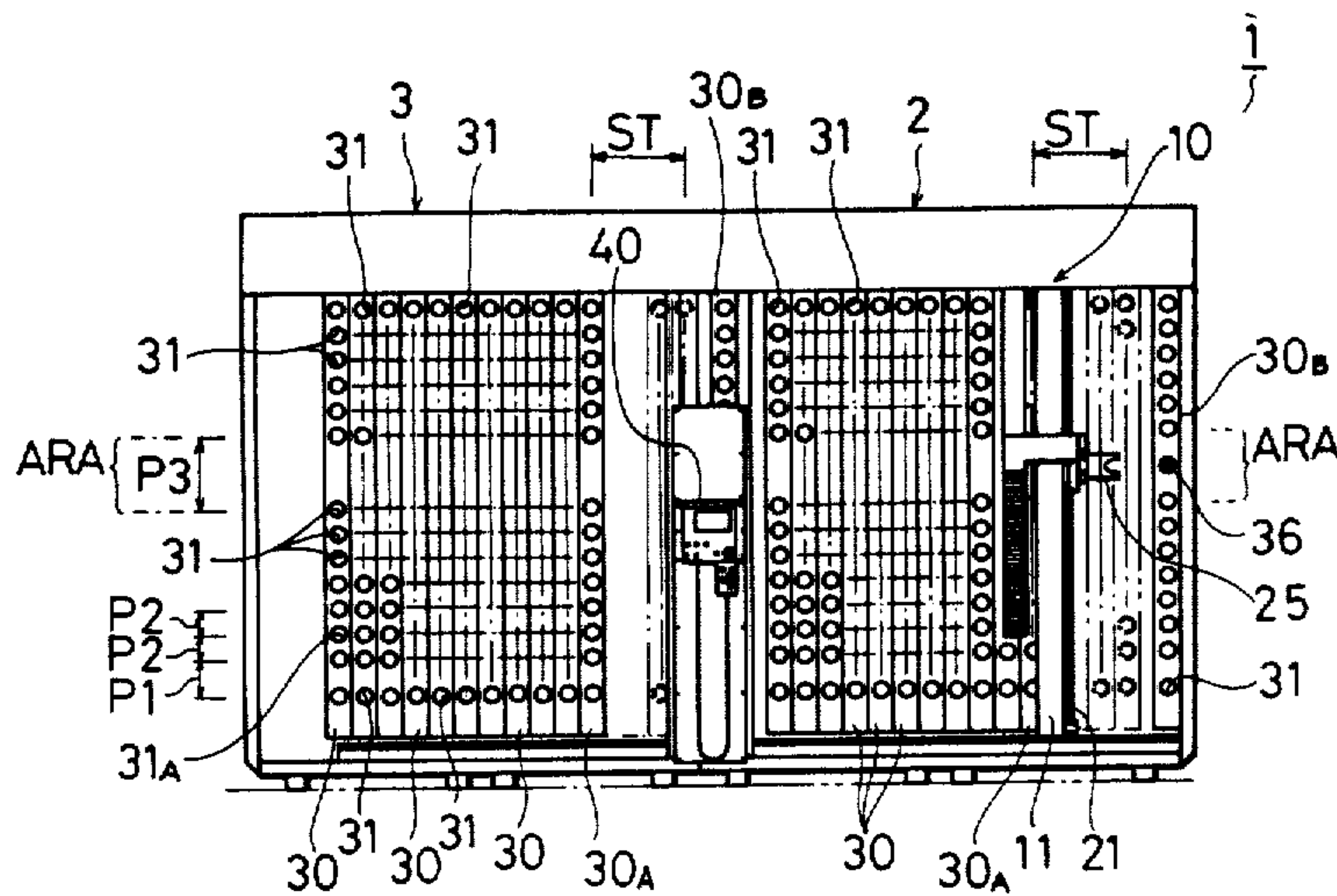
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Primary Examiner—William R. Briggs
Attorney, Agent, or Firm—Cushman, Darby & Cushman

[57] ABSTRACT

A tool storing and feeding apparatus is disclosed. It includes a plurality of tool racks in the shape of a band plate designed to be movable. The tool racks are provided with a plurality of tool pockets arranged in their longitudinal direction. An intermediate feed pocket for delivering and feeding tools to a machine tool, and means for delivering and feeding tools are provided. Tools to be fed to the machine tool are put in the tool pockets. The tools put in the tool pockets are delivered between the intermediate feed pocket and the tool racks.

7 Claims, 18 Drawing Figures



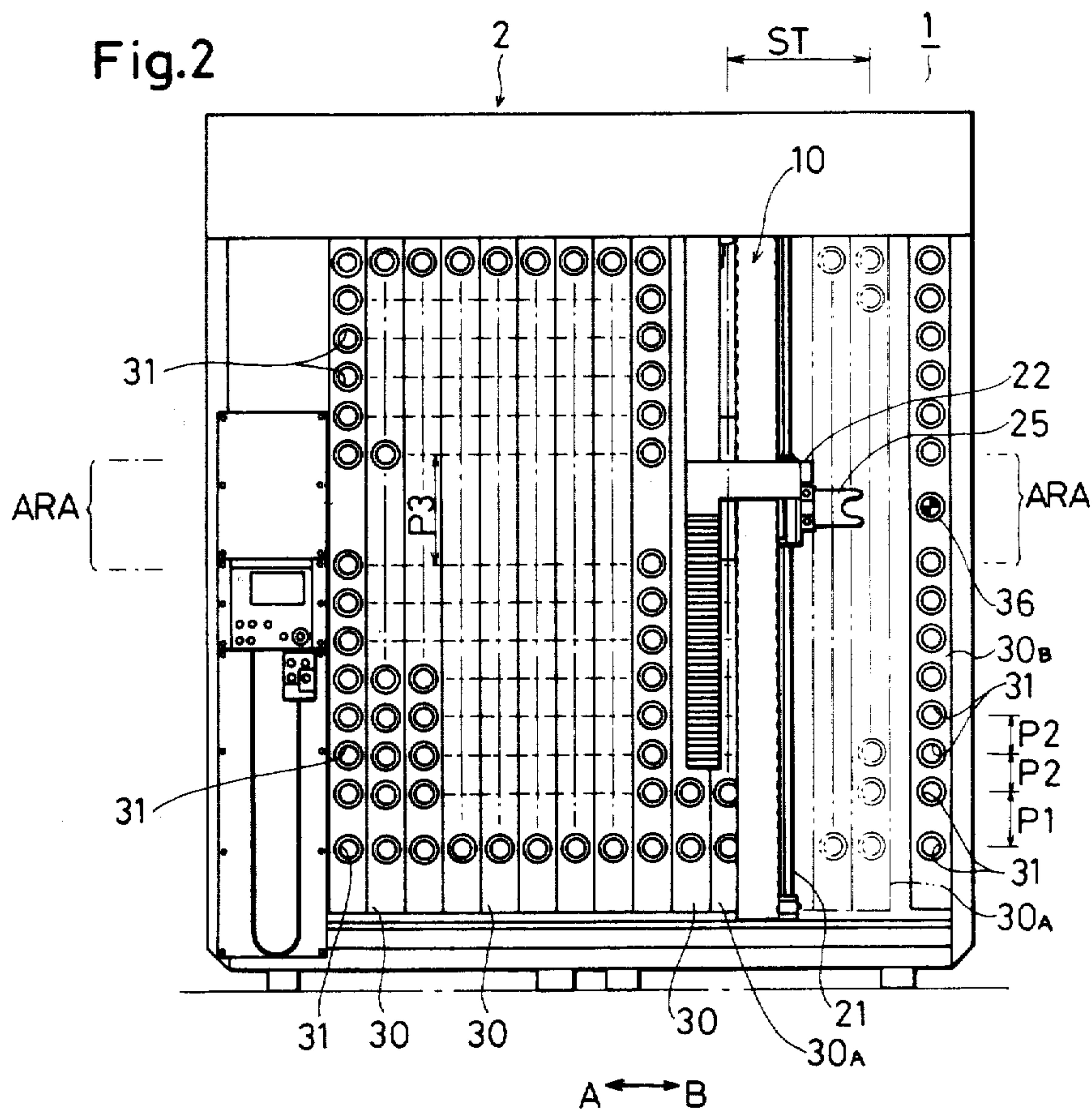
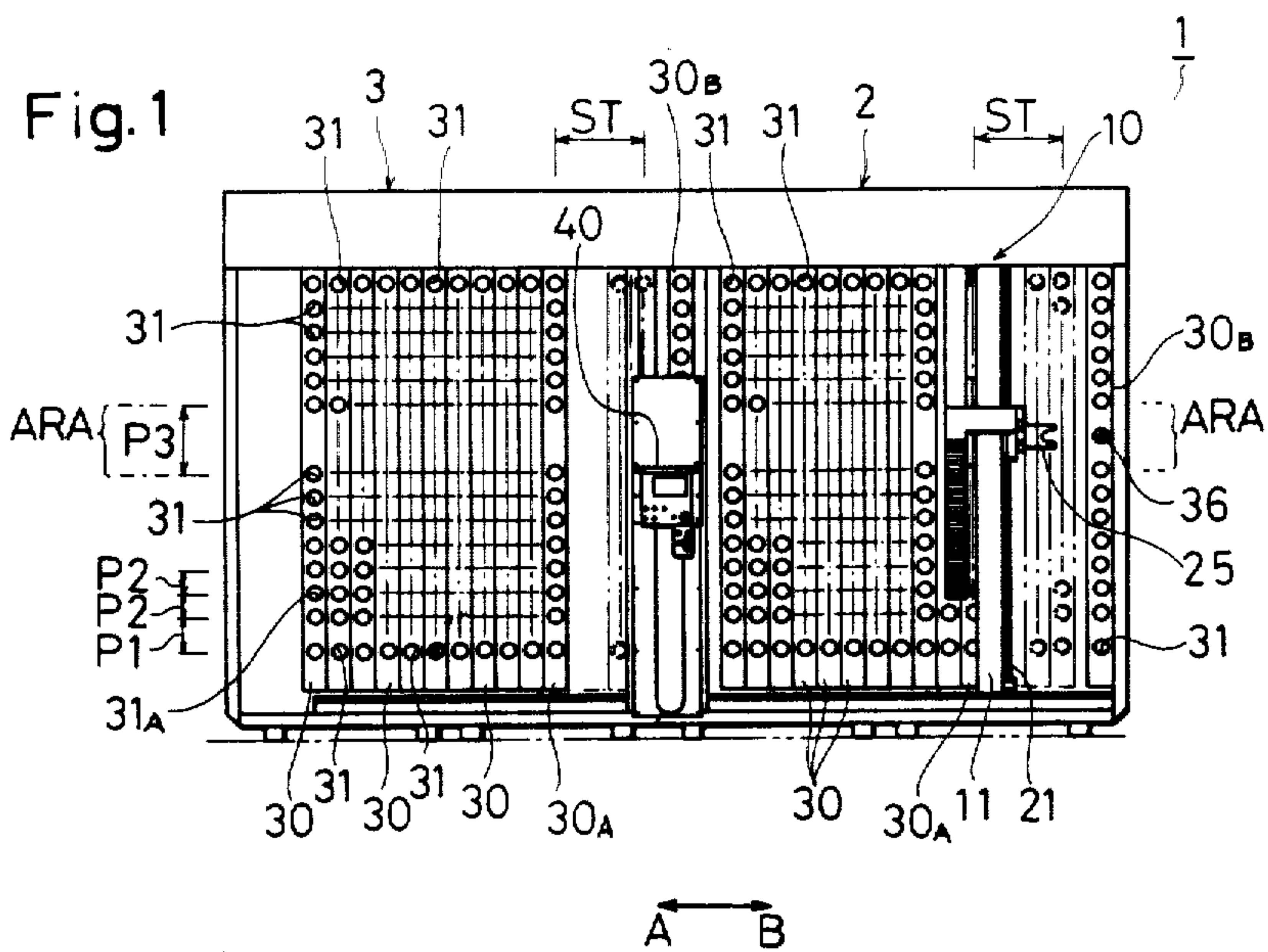


Fig.3

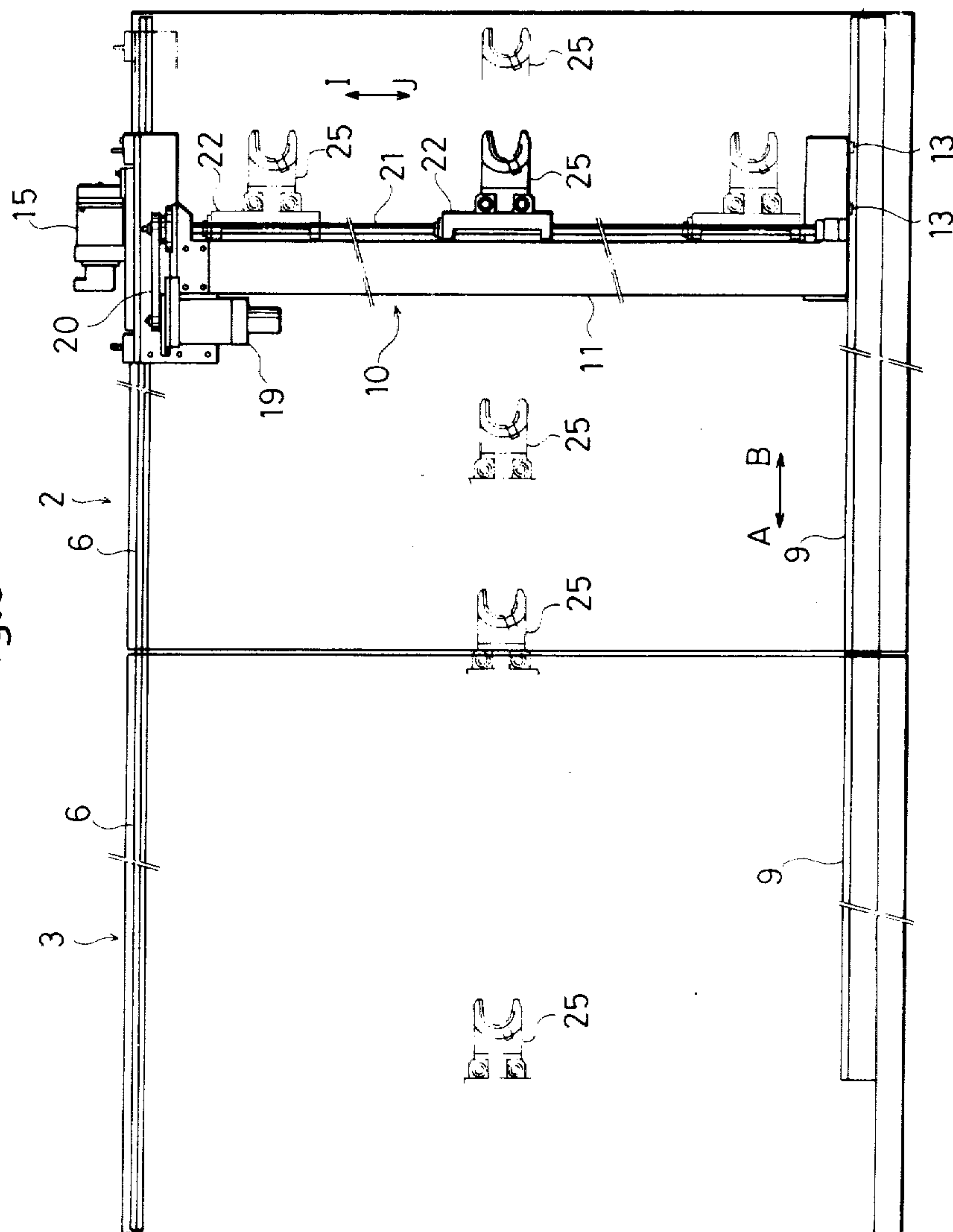


Fig.4

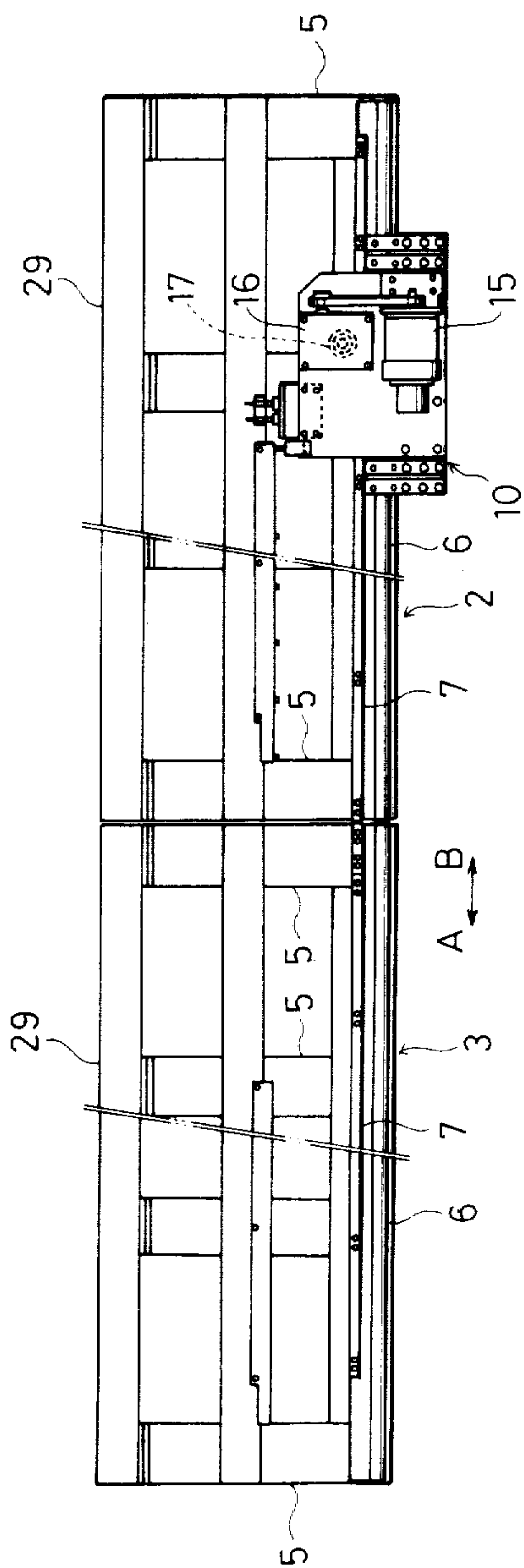


Fig. 5

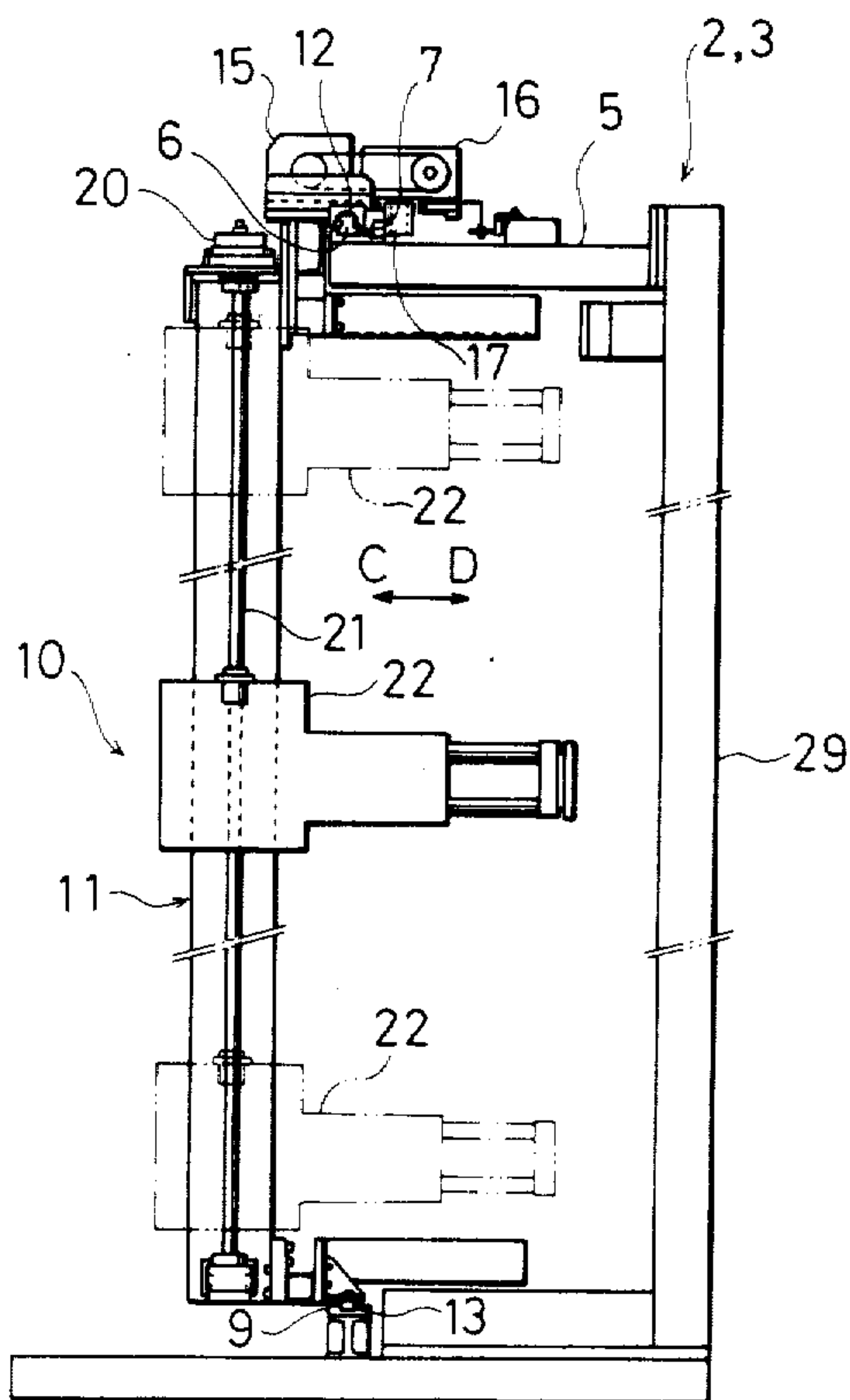


Fig.6

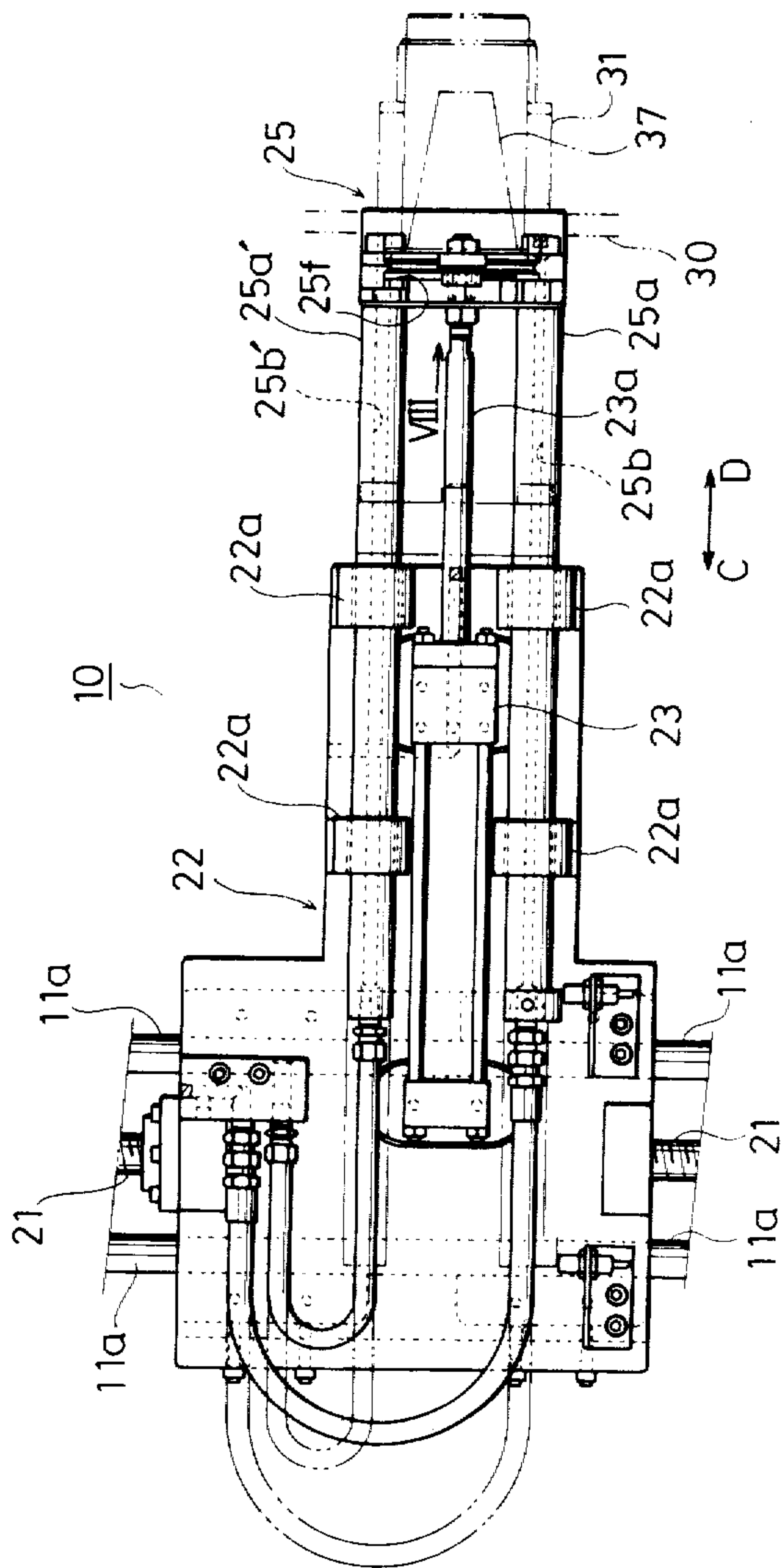


Fig.7

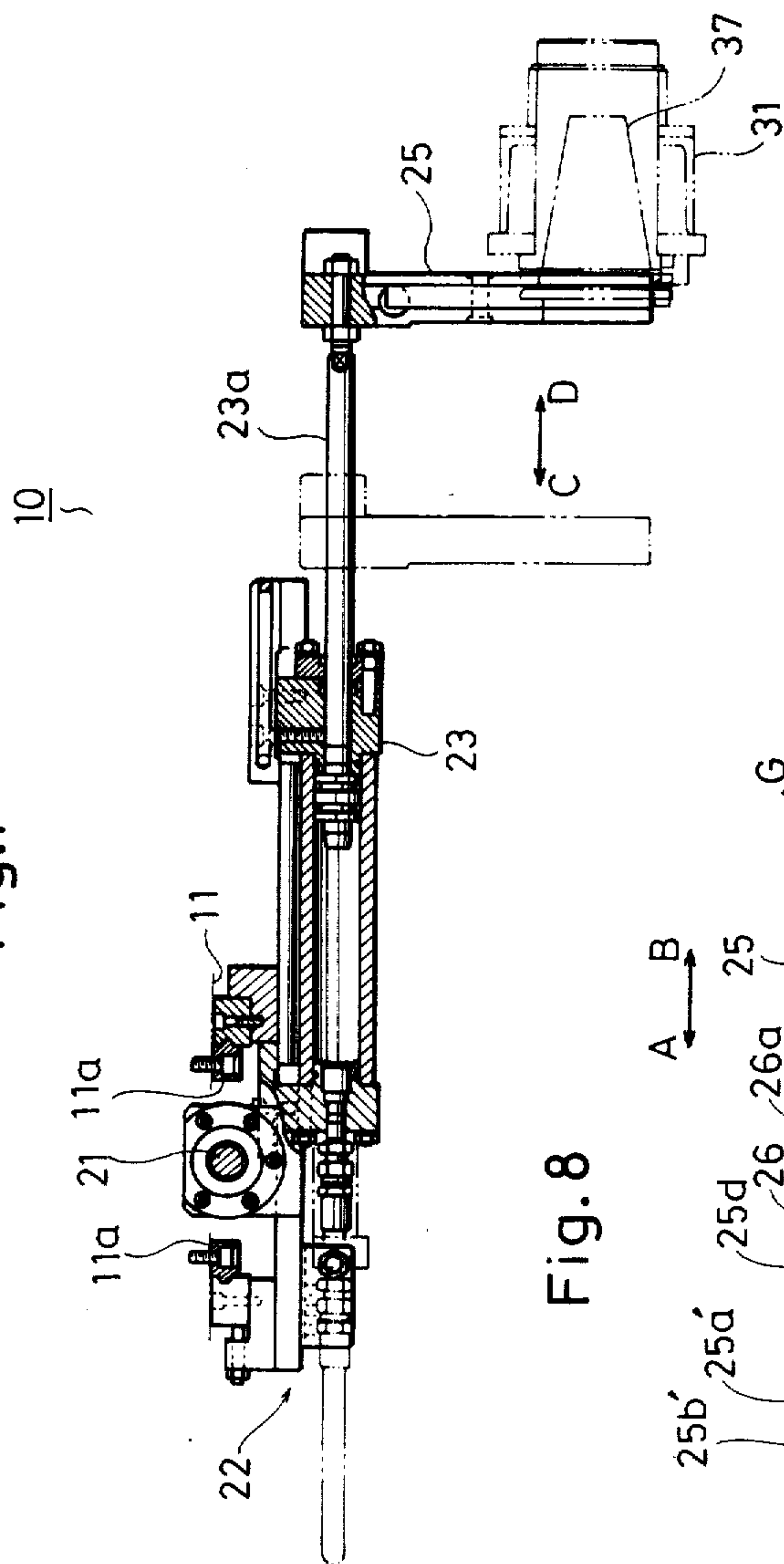
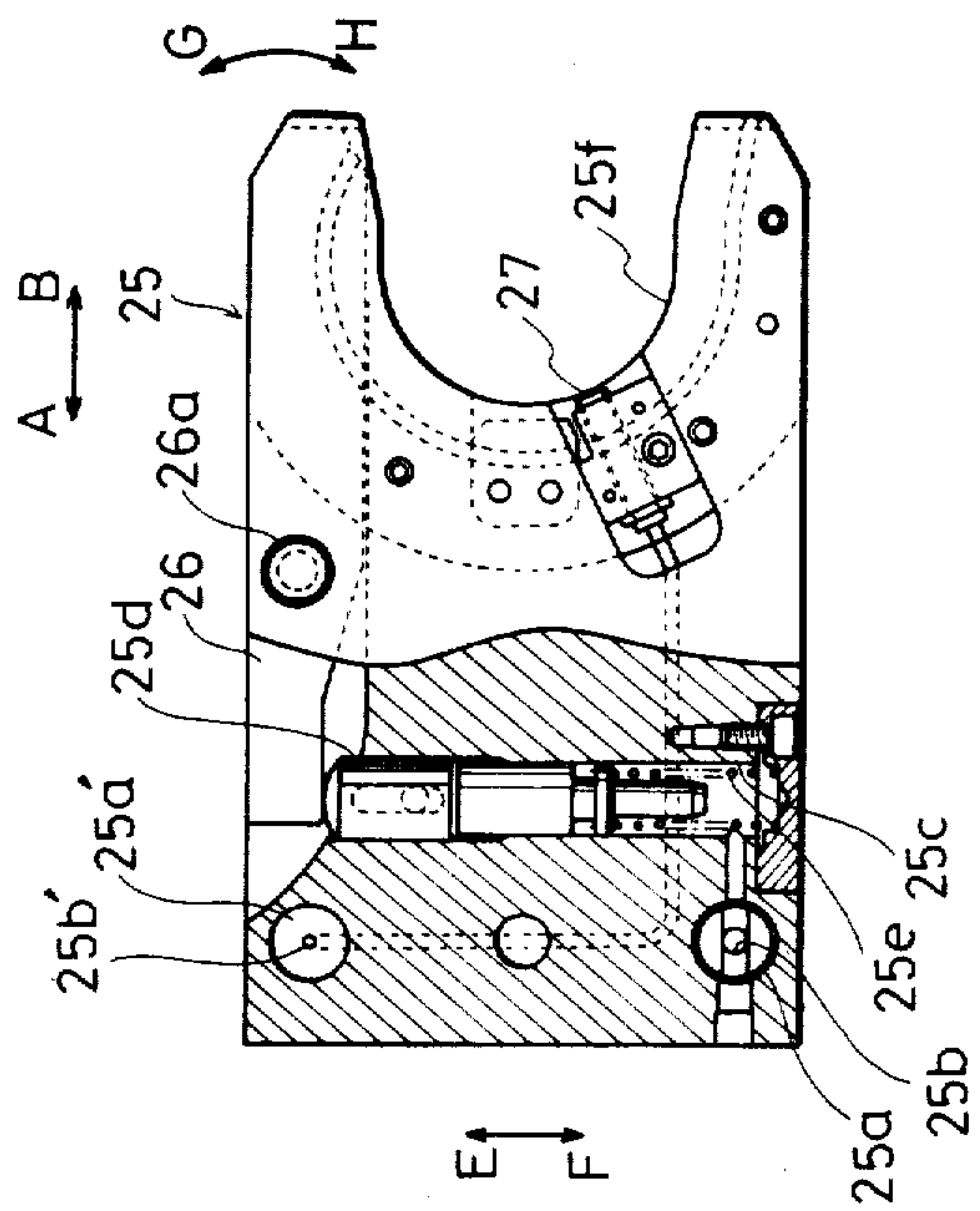
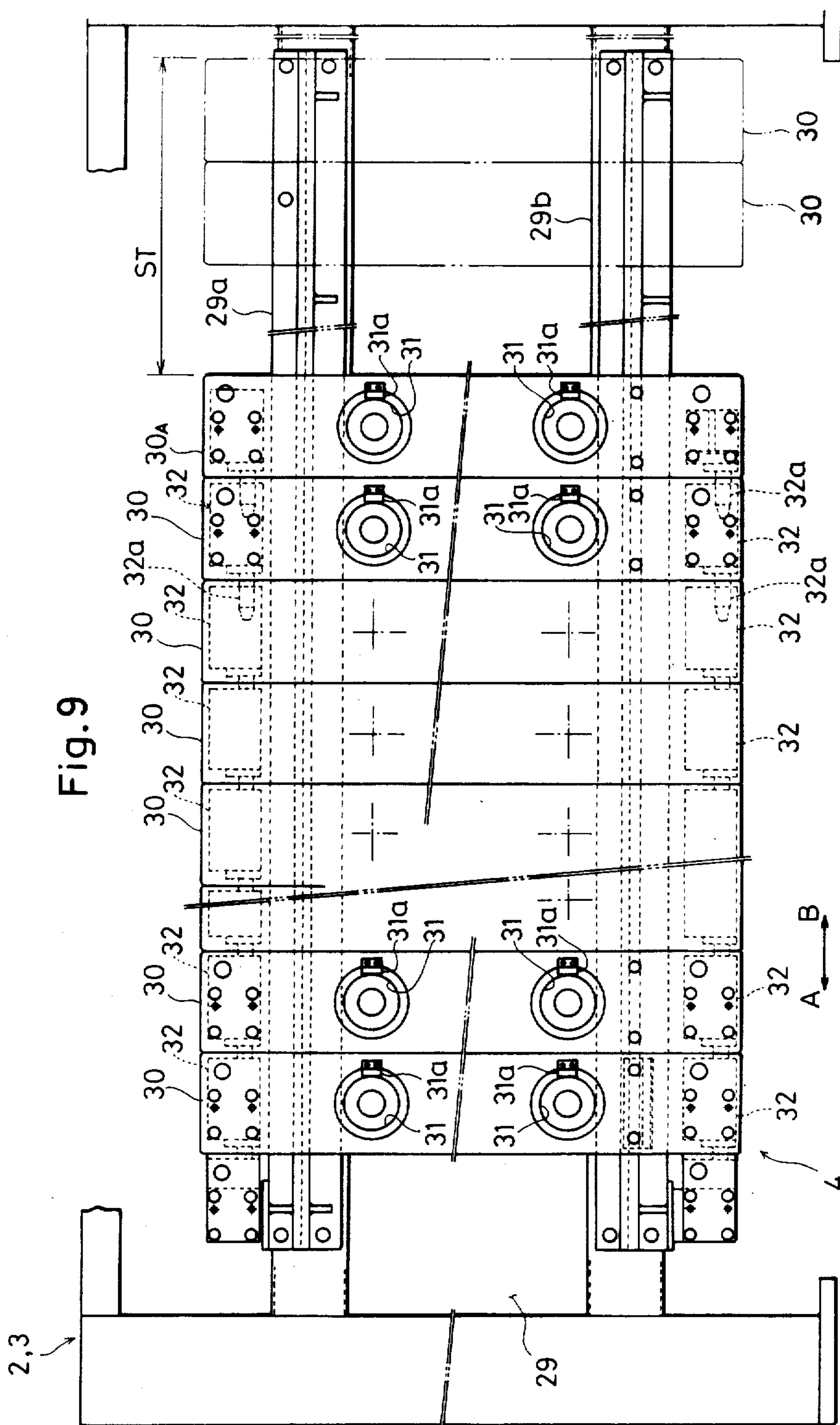


Fig.8





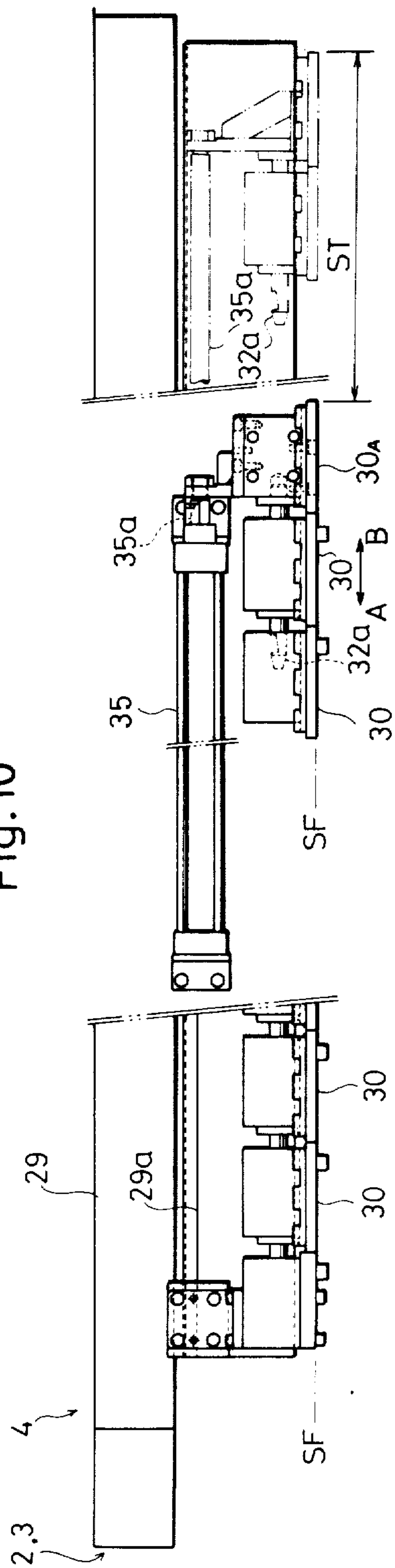


Fig. 10

Fig.11

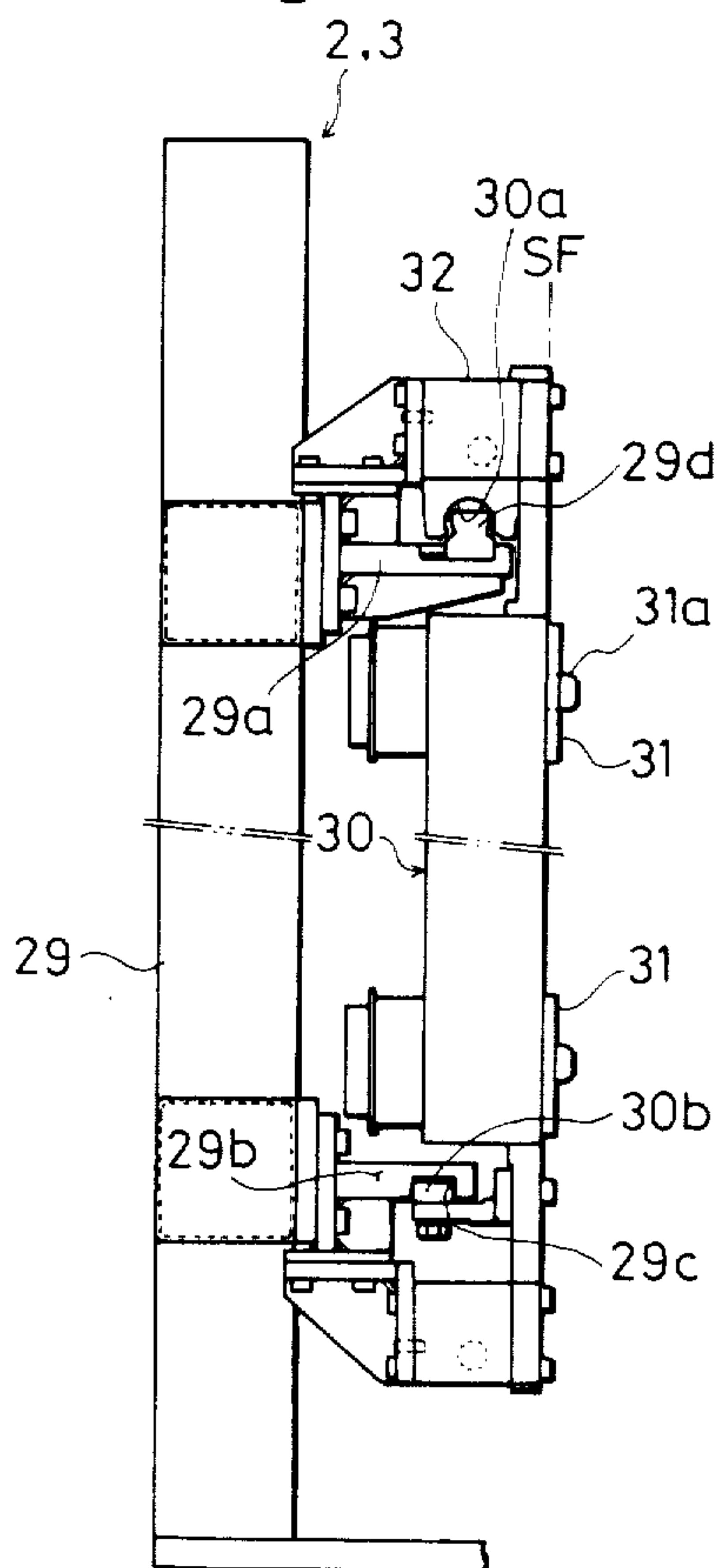
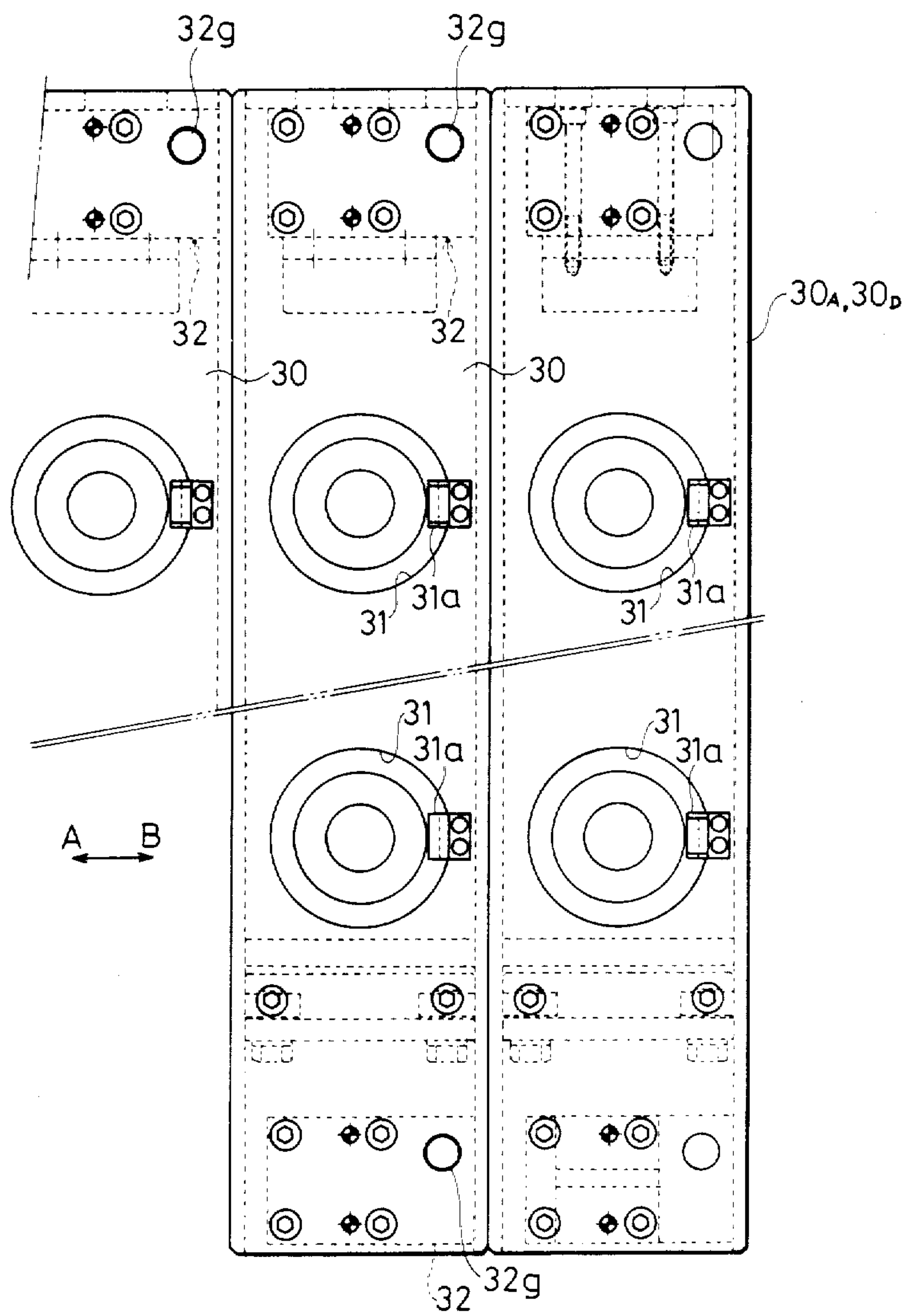


Fig.12



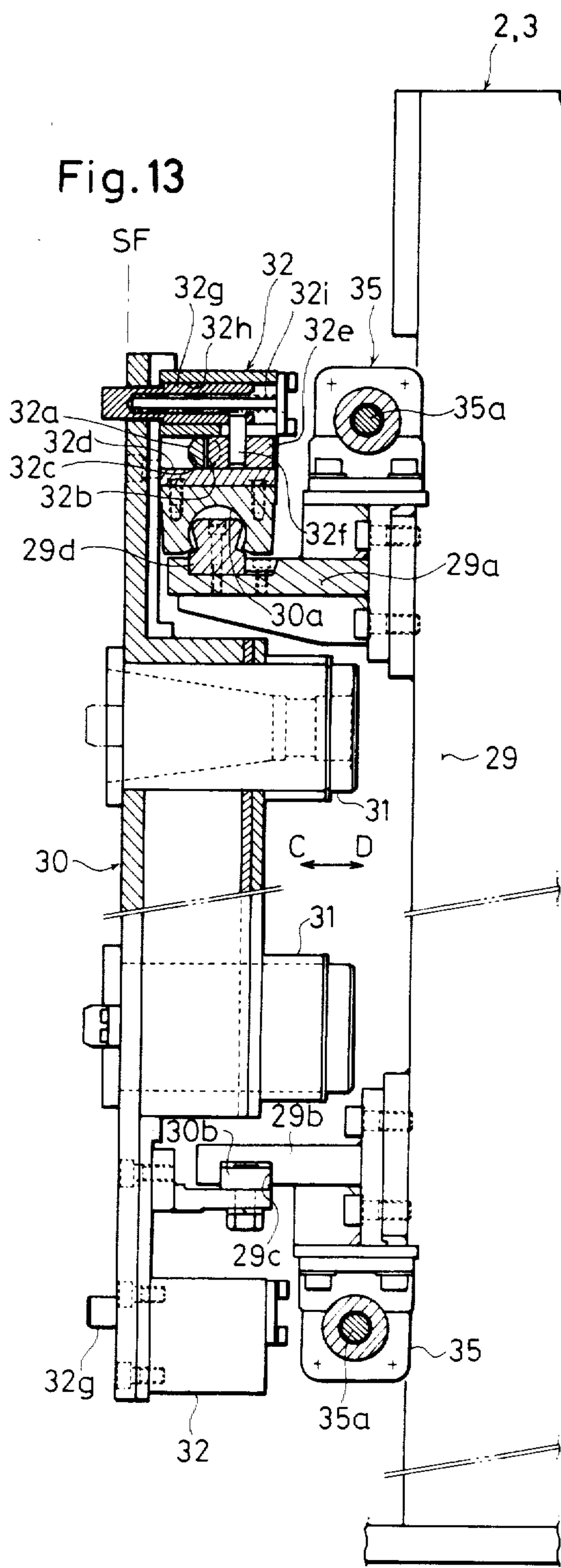


Fig. 14

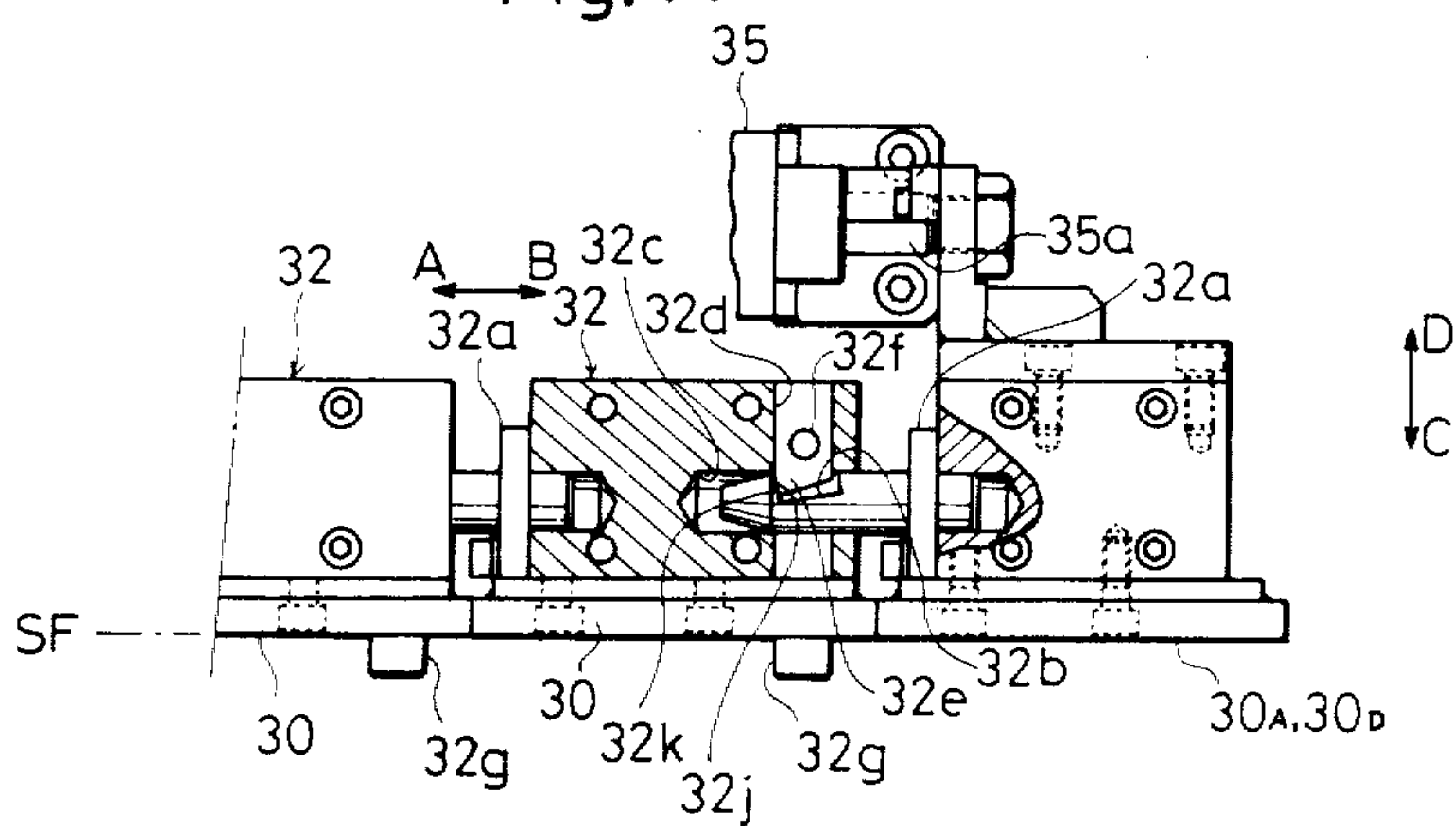


Fig. 15

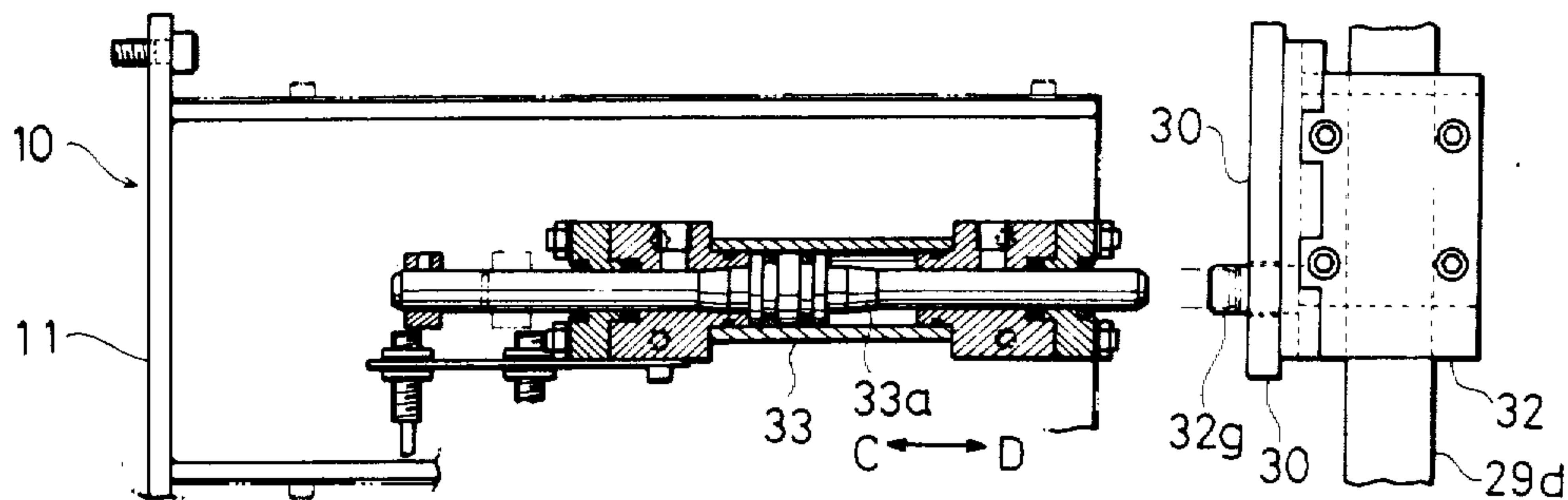


Fig. 16

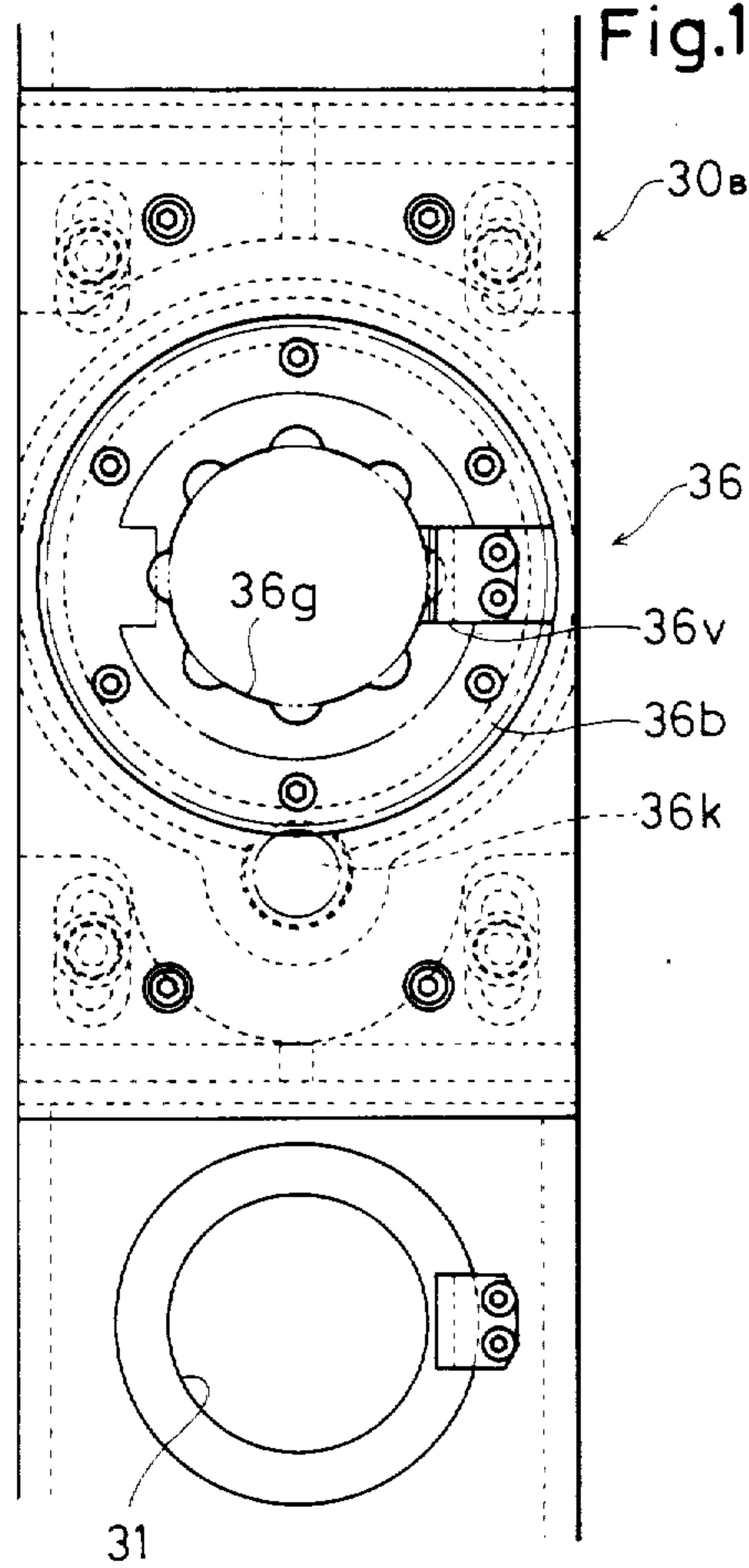


Fig.17

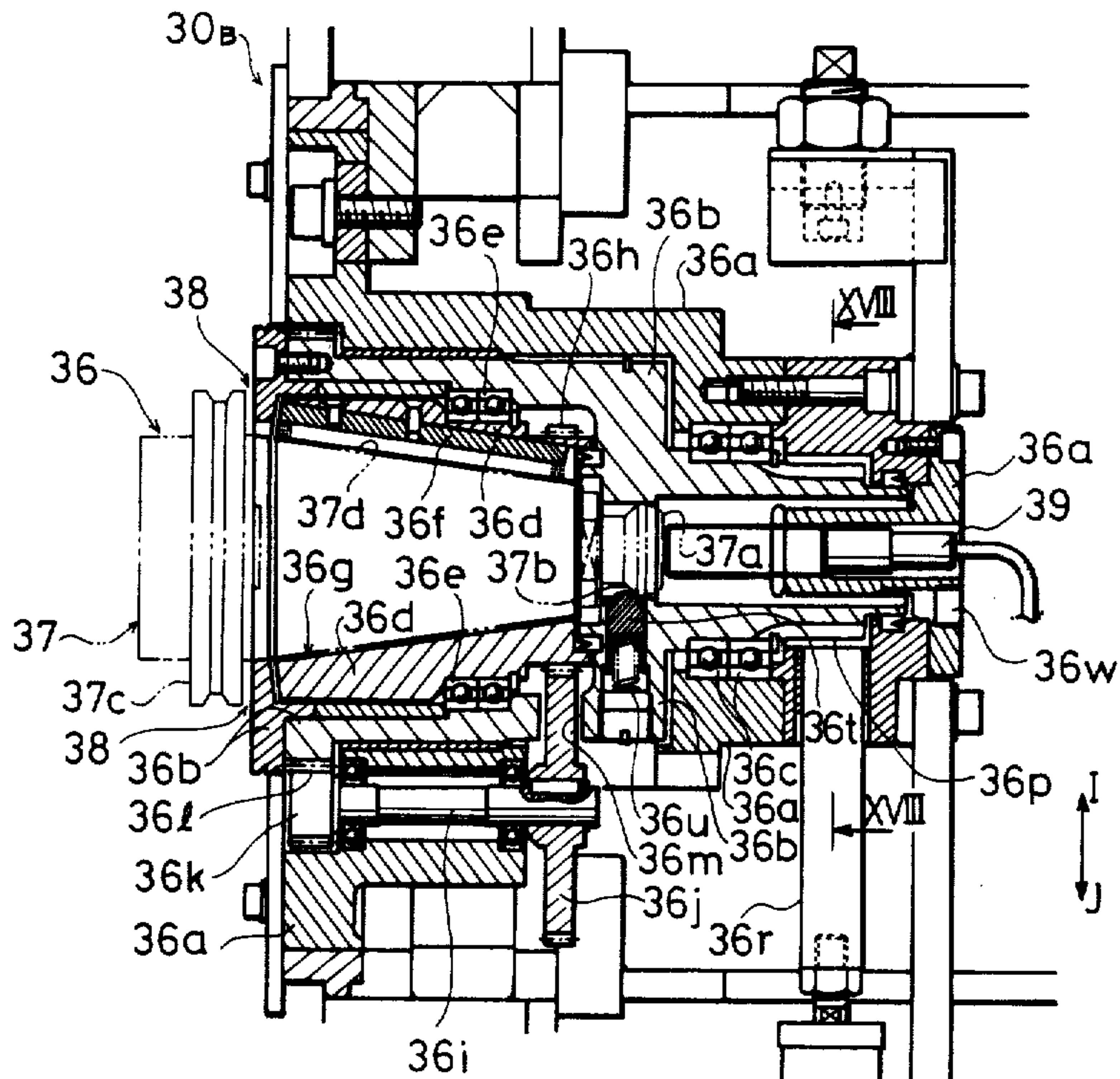
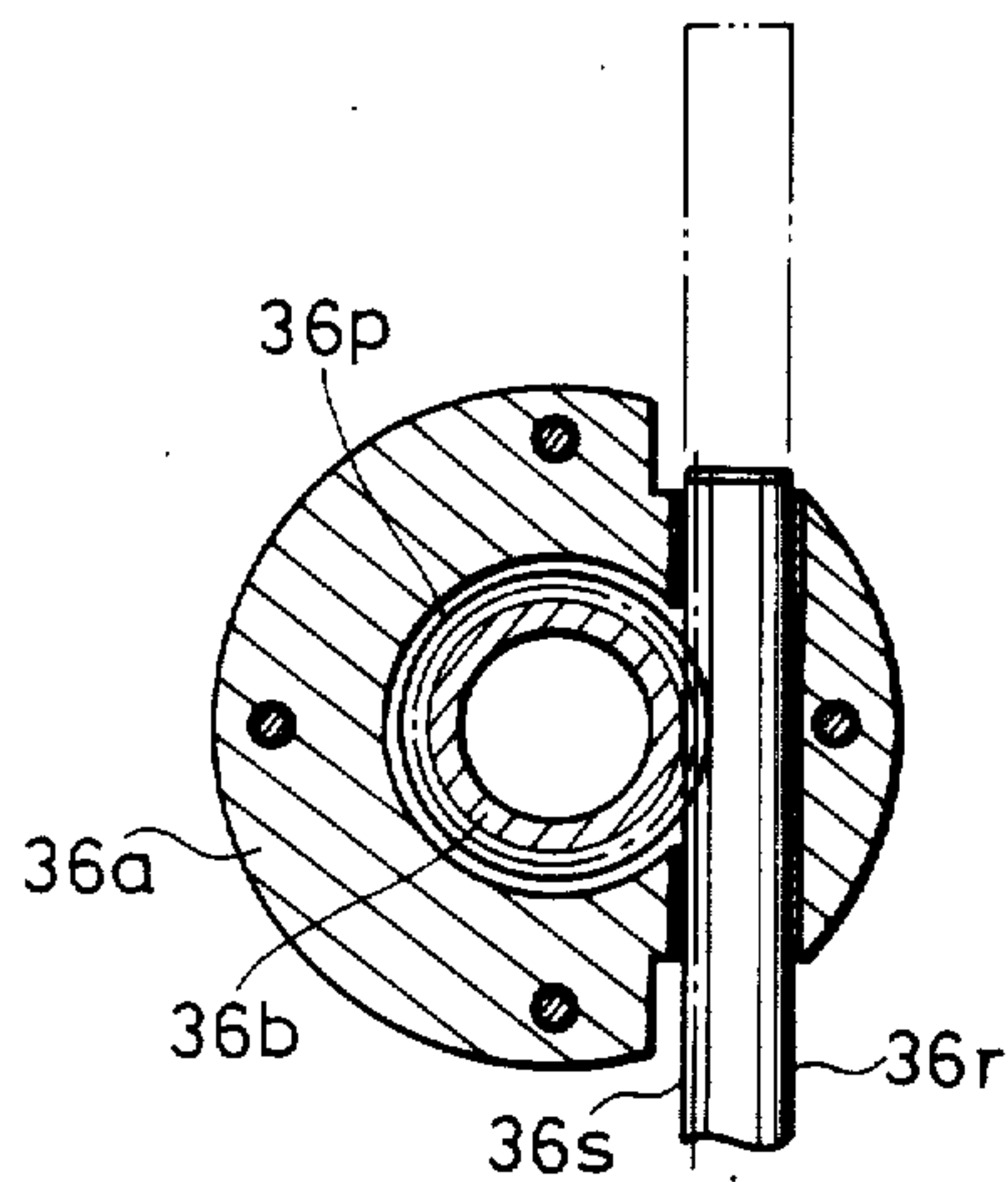


Fig.18



TOOL STORING AND FEEDING APPARATUS**CROSS REFERENCE TO RELATED APPLICATION**

The subject matter of this application is generally related to the subject matter of Ser. No. 762,836, filed Aug. 6, 1985, for TOOL STORING APPARATUS, although there is a clear line of demarcation between the claims of the two applications.

BACKGROUND OF THE INVENTION

This invention relates to a tool storing and feeding apparatus for feeding tools to a machine tool such as a machining center and the like, and a method thereof.

Heretofore, a drum-shaped tool magazine, a chain type tool magazine, etc. are known as a tool storing and feeding apparatus of the type set forth above. However, they are limited to several tens in number of tools which they can store and feed.

In recent years, however, a machining by machine tool without using a man power has been prevailed. In such a case, in order to process a number of various kinds of works, tools which are required to feed to a machine tool is increased in number tremendously. Therefore, conventional tool storing and feeding apparatuses which are capable of feeding only several tens of tools are no more effective in performing a satisfactory processing work.

In view of the foregoing, there are proposed several types of tool storing and feeding apparatuses. One such example is of the type which includes a plurality of tool magazines of a drum shape, wherein a number of tools are fed while replacing the magazines with respect to a machine tool. Another example is a chain type tool magazine, wherein the length of a chain is extended in order to store a number of tools. A still further example is of the type, wherein a plurality of chain type tool magazines are arranged in a parallel relation. However, they still have such a disadvantage as that they are not practical when used for feeding from one hundred to several hundreds of tools, since many problems are involved, e.g. that a long time is required for feeding the tools to the machine tool, that a large space is required for installation thereof, etc.

Also, another effective proposal is of the type, wherein tools are stored in a storing shelf formed in three dimensions beforehand, and the tools are delivered to a machine tool by a delivery robot. However, in this type, it is required to keep sufficient spaces among the tools stored on the shelf in order to avoid interference between the robot and the adjacent tools at a time when a tool is taken out and stored. In addition to the foregoing, a sufficient space is required to maintain between the travelling position of the delivery robot and the storing position of the tools on the shelf in order to avoid interference between the travelling robot and the tools stored on the shelf, which prohibits the tools to store in high density. Therefore, where hundreds of tools are required to store, there often arises an installation space problem.

SUMMARY OF THE INVENTION

It is therefore a first object of the present invention to provide a tool storing and feeding apparatus, wherein a large number of tools can be stored in high density and

therefore in a limited space, and the tools can be fed to a machine tool promptly, too.

A second object of the present invention is to provide a tool storing and feeding apparatus, wherein no interference is occurred between tool delivery means, and tools.

A third object of the present invention is to provide a tool storing and feeding apparatus including means for delivering and feeding tools which is capable of effectively handling tools with respect to means for storing the tools.

A fourth object of the present invention is to provide a tool storing and feeding method which is capable of preventing occurrence of interference between tools and means for delivering and feeding the tools in advance, so that a large number of tools can be stored in high density and therefore in a limited space, and the tools can be fed to a machine tool promptly, too.

That is, the present invention includes a plurality of tool racks in the shape of a band plate, each tool rack being movably provided, said tool racks being provided with a plurality of tool pockets for storing tools therein arranged in the longitudinal direction thereof, an intermediate feed pocket for delivering and feeding tools to a machine tool, and means for delivering and feeding tools between said tool racks and said intermediate pocket.

Also, according to an embodiment of the present invention, said tool racks are provided with a travelling area of said delivery and feed means where the tool pockets are not provided and which is extended transversing the respective tool racks, said delivery and feed means being movable through said travelling area.

Furthermore, the present invention is constituted as such that in a tool storing and feeding apparatus including a frame provided with a plurality of tool storing means developed on a plane, said frame being provided with travel guide means parallel to the plane on which the tools are developed, said travel guide means being movably provided with a main body of said means for delivering and feeding tools, said main body being movably provided with a hand mechanical portion in the vertical direction of said main body and in parallel with said plane, said hand mechanical portion being reciprocally projectably provided with a tool grasping member for grasping tools with respect to said storing means.

Furthermore, a method according to the present invention comprises including a plurality of tool racks in the shape of a band plate movably provided, arranging a plurality of tool pockets for storing tools therein on said tool racks in the longitudinal direction thereof; further providing means for delivering and feeding tools, arranging said tool racks side by side in a continuous manner under normal storing state of the tools, but when a tool is to be attached to and detached from a predetermined tool pocket, moving the tool racks separating from the tool rack on which said tool pocket is provided, so that a space is formed between the tool rack for said tool to be attached thereto and detached therefrom, and one of the tool racks adjacent to said tool rack, performing the attaching and detaching operation of the tool with respect to said tool pocket by said delivery and feed means utilizing said space while avoiding occurrence of interference between said delivery and feed means and said tool rack and other tools.

Constitutions of other preferred embodiments will be described in the following detailed description of the embodiments.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is a front view showing one embodiment of the present invention applied to a tool storing and feeding apparatus;

FIG. 2 is a front view showing a main frame portion of the tool storing and feeding apparatus of FIG. 1;

FIG. 3 is a front view showing a tool robot portion;

FIG. 4 is a plan view of FIG. 3;

FIG. 5 is a side view of FIG. 3;

FIG. 6 is a front view showing a hand portion of the tool robot;

FIG. 7 is a plan view of FIG. 6;

FIG. 8 is a view of a tool grasping member when viewed from the direction as shown by the arrow VIII in FIG. 6;

FIG. 9 is a front view of a tool rack portion;

FIG. 10 is a plan view of FIG. 9;

FIG. 11 is a side view of FIG. 9;

FIG. 12 is a front view showing a connected state of the tool racks;

FIG. 13 is a side view of FIG. 12;

FIG. 14 is a plan view of FIG. 12;

FIG. 15 is a plan view showing an unlocking mechanism of the tool robot;

FIG. 16 is a front view showing an intermediate feed pocket;

FIG. 17 is a side view of FIG. 16; and

FIG. 18 is a sectional view taken on line XVIII-XVIII of FIG. 17.

DESCRIPTION OF THE PREFERRED EMBODIMENTS

A tool storing and feeding apparatus 1, as shown in FIG. 1, includes a main frame 2 and a sub-frame 3 connected to the left part of the main frame 2. The main frame 2 and the sub-frame 3 are, as shown in FIG. 5, formed with a bracket 5 at the upper portions thereof. Disposed at a tip portion of the bracket 5 is a guide rail 6 extending in the right and left direction in FIGS. 3 and 4 transversing the main frame 2 and the sub-frame 3. The bracket 5 is further provided with a rack 7 disposed likewise in the right and left direction in FIGS. 3 and 4 along the guide rail 6. Also, the main frame 2 and the sub-frame 3 are provided at the lower portions thereof with a guide rail 9 in parallel with the guide rail 6. A tool robot 10 serving as means delivering and feeding tools is movably mounted on the guide rails 6 and 9 for movement in the directions as shown by arrows A and B in FIG. 3 through a guide groove 12 and a guide roller 13 which are provided in a main body 11 of the tool robot 10. The main body 11 is provided at its upper portion with a motor 15. The motor 15 is rotatably provided with a pinion gear 17 through power transmitting means such as a speed reducing apparatus 16, etc. The pinion gear 17 is meshed with the rack 7. Accordingly, the main body 11 is moved in the directions as shown by the arrows A and B along the rack 7 guided by the guide rails 6 and 9 in accordance with normal and reverse rotation of the motor 15 through the speed reducing apparatus 16 and the pinion gear 17.

Also, the main body 11 is provided with a motor 19. The motor 19 is connected at its upper end portion to a feed screw 21 rotatably supported by the main body 11 in the vertical direction in FIG. 3, through power transmitting means such as a timing belt 20, etc. The feed screw 21 is threadedly engaged with a hand mechanical portion 22. The hand mechanical portion 22 is movably

engaged with a pair of guide rails 11a formed in parallel with the feed screw 21 on the main body 11 for movement in the right perpendicular direction with respect to the paper surface in FIG. 7, that is, in the disposed direction of the feed screw 21. The hand mechanical portion 22 is provided with a hydraulic cylinder 23 with a piston rod 23a for reciprocally projecting in the directions as shown by arrows C and D. Moreover, the hand mechanical portion 22 is provided, as shown in FIG. 6, with a plurality of slide bearings 22a. The slide bearings 22a are movably provided with a tool grasping member 25 for movement in the directions as shown by the arrows C and D, through guide rods 25a and 25a' slidably mounted on the slide bearings 22a. The guide rods 25a is formed with a through-hole 25b along its center for feeding pressure oil to the tool grasping member 25. Furthermore, the guide rod 25a' is formed with a hole 25b' for containing a cord to be connected to a proximity sensor as will be described later. A front end of the piston rod 23a is fixedly secured to the tool grasping member 25.

Also, the tool grasping portion 25 is formed, as shown in FIG. 8, with a cylinder 25c communicating with the hole 25b formed in the guide rod 25a. The cylinder 25c is movably provided with a piston 25d for movement in the directions as shown by arrows E and F. Interposed between the piston 25d and the cylinder 25c is a coil spring 25e in its depressed state for normally energizing the piston 25d in the direction as shown by an arrow E. Also, the tool grasping portion 25 is pivotably provided with an arm 26 for pivoting in the directions as shown by the arrows G and H through a pin 26a. The left end of the arm 26 in FIG. 8 is in abutting contact with the front end of the piston 25d. Furthermore, the tool grasping portion 25 is provided with a proximate sensor 27 with its front end facing toward a tool grasping groove 25f formed in the tool grasping member 25 in a generally U-shape. The proximate sensor 27 is adapted to detect whether a tool is in the tool grasping groove 25f. On the other hand, a side plate 29 of the main frame 2 and the sub-frame 3 is provided, as shown in FIGS. 9 and 11, at its upper and lower portions with brackets 29a and 29b, respectively, in the travelling directions of the tool robot 10 as shown by the arrows A and B. The lower bracket 29b is formed with a guide groove 29c extending in the directions A and B. Furthermore, the upper bracket 29a is provided with a guide rail 29d likewise extending in the directions A and B. A plurality of tool racks 30 in the shape of an elongated band plate are movably supported by the guide rail 29d and the guide groove 29c for movement in the directions A and B, with a guide groove 30a and a guide roller 30 provided at the tool racks 30 engaged with the guide rail 29d and the guide groove 29c. Each of the tool racks 30 is provided with a plurality of tool pockets 31 for holding tools arranged in a row in the vertical direction of FIG. 9, that is, in the longitudinal direction of the tool rack 30.

Location pitches of the respective tool pockets 31 are set as such that the location pitch P1 between the lowest tool pocket 31 and the next lowest tool pocket 31 in FIGS. 1 and 2 is larger than the location pitch P2 between tool pockets 31 thereabove. Accordingly, the lowest tool pocket 31 in the figures is capable of storing a tool 37 of a large diameter. Also, two tool pockets 31 formed at the central portion of each of the tool racks 30 are spacedly located with a distance P3 therebetween. In the case a plurality of tool racks 30 are ar-

ranged side by side in a continuous manner as shown in FIGS. 1 and 2, a tool robot travelling area ARA is formed at the central portion of each of the tool racks 30 in the direction transversing the respective tool racks 30.

Also, each of the tool pockets 31 is, as shown in FIG. 9, provided with a locking key 31a which is engaged in a key groove formed in the tool side thereof for preventing rotation of a tool in the tool pocket 31.

Also, each of the tool racks 30 is provided at its upper and lower portions with a connecting mechanism 32, as shown in FIGS. 12 through 14, for connecting the tool racks 30 one another. The connecting mechanism 32 has a pin 32a fixed, with its front end projecting to the adjacent tool rack 30 to be connected. The front end portion of the pin 32a is formed with an engaging groove 32b as shown in FIG. 14. Also, the adjacent tool rack 30 is formed at a position opposite to the pin 32a with an engaging hole 32c so that the pin 32a is engaged therein. The engaging hole 32c is formed with a hole 32d in the perpendicular direction with the engaging hole 32c as shown in FIG. 13. Movably engaged in the hole 32d is a lock pin 32e for movement in the directions as shown by the arrows C and D. The lock pin 32e is planted therein with a pin 32f. The pin 32f is engaged in an unlocking pin 32g movably inserted in a hole 32h formed in parallel with the hole 32d at its upper location in FIG. 13 for movement in the directions as shown by the arrows C and D. Interposed between the unlocking pin 32g and the hole 32h is a coil spring 32i in its depressed state for normally energizing the unlocking pin 32g in the direction as shown by the arrow C.

The main body 11 of the tool robot 10 is provided, as shown in FIG. 15, at its upper and lower portions to be capable of opposing to the connecting mechanism 32 of the tool rack 30 with a unlocking cylinder 33 with its piston rod 33a reciprocally projecting in the directions as shown by the arrows C and D.

Among the tool racks 30 movably provided on the main frame 2 and the sub-frame 3, the tool racks 30_A at the second from the rightmost in FIG. 1, which are mounted on the respective frames are connected at the upper and lower portions thereof, as shown in FIG. 10, with a rack opening cylinder 35 mounted on a side plate 29 through a piston rod 35a for reciprocally projecting in the directions as shown by the arrows A and B. Accordingly, the tool racks 30_A are reciprocally moved in the directions A and B along the guide rail 29d etc. when the piston rod 35a is caused to reciprocally project in the directions A and B driven by the rack opening cylinder 35.

The tool racks 30_B, 30_B at the rightmost in FIG. 1 each on the main frame 2 and the sub-frame 3 are fixed to the side plate 29 respectively. The tool rack 30_B on the main frame 2 is provided with an intermediate feed pocket 36 at a generally central portion thereof corresponding to the tool robot travelling area ARA of other tool racks 30. The intermediate feed pocket 36 has a frame 36a fixedly secured to the tool rack 30_B as shown in FIGS. 16 and 17. A rotary holder 36b is rotatably mounted on the frame 36a through a bearing 36c, etc. Furthermore, a cleaning holder 36d is rotatably mounted on the rotary holder 36b through a bearing 36e. The cleaning holder 36d is provided with a cleaning brush 36f, with the brush portion at its front end projecting to a tool holding portion 36g formed thereon in the shape of a cut cone. The cleaning holder 36d is formed on the outer periphery thereof with a gear 36h.

The gear 36h is meshed with a gear 36j mounted on a shaft 36i rotatably supported by the frame 36a through a slit 36m formed in the rotary holder 36b. The other end of the shaft 36i is provided with a gear 36k which meshes with a gear 36l formed at the left end portion on the rotary holder in FIG. 17. Also, the rotary holder 36b is formed at the right end portion in the figure with a pinion gear 36p. The pinion gear 36p is meshed, as shown in FIG. 18, with a rack 36r formed on a bar-shaped rod 36r which is projectable by a cylinder 36q in the directions as shown by the arrows I and J. Also, the rotary holder 36b is movably provided with a lock pin 36t for movement in the directions as shown by the arrows I and J in FIG. 17. The lock pin 36t is energized by a coil spring 36u in the direction as shown by an arrow I. The lock pin 36t is engaged in a groove portion 37b of a pull stud 37a of a tool 37 held by the tool holding portion 36g by using an elastic property of the coil spring 36u, so that the tool 37 inserted in the tool holding portion 36g is prevented from coming off unexpectedly. Reference numeral 39 denotes a proximate sensor for detecting whether the tool 37 is inserted in the tool holding portion 36g.

Since the tool storing and feeding apparatus 1 has the above mentioned construction, feed of the tools 37 from the tool storing and feeding apparatus 1 to a machine tool such as a machining center (not shown) or the like is performed in the following manner. Firstly, based on a machining program and an operator's instructions, the tool robot 10 is suitably moved in the directions as shown by the arrows A and B in FIG. 3 along the guide rails 6 and 9 laid down on the main frame 2 and the sub-frame 3. This movement is effected by the speed reducing apparatus 16, the pinion gear 17 and the rack 7 meshed with the pinion gear 17 by properly rotating the motor 15 on the main body 11 of the tool robot 10 either in the normal direction or in the reverse direction, as already described. The tool robot 10 is driven so far as to a position opposite to a tool rack 30 with a tool 37 to be fed to the machine tool in the directions A and B. Since the tool robot 10 travels with its hand mechanical portion 22 held in vertically alignment with the tool robot travelling area ARA where no tool pockets 31 are located, the hand mechanical portion 22 of the tool robot 10 travelling in the directions A and B is not interfered with the tools 37 stored in the respective tool racks 30, thereby ensuring the tool robot 10 to travel smoothly. Since the guide rails 6 and 9 are laid down penetrating through the main frame 2 and the sub-frame 3 as already described, the tool robot 10 can freely travel between the main frame 2 and the sub-frame 3.

On the other hand, the tools 37 to be fed are stored in the tool pockets 31 of the respective tool racks 30 (in this embodiment, 14 tools 37 are stored per each of the tool racks 30). The tool racks 30 with the tools stored therein are, in normal state, integrated one another (excepting the tool racks 30_B, 30_B at the rightmost of the respective frames) as shown in FIG. 9, since the adjacent tool racks 30 are interconnected by the connecting mechanism 32. This integration of the tool racks 30 is made per the main frame 2 and the sub-frame 3 as one unit, respectively. Accordingly, other tool racks 30 than the tool racks 30_B at the right extreme of the respective frames fixed to the respective main frame 2 and sub-frame 3 are, when in the connected state, moved along the guide rail 29d and the guide groove 29c as one body, respectively, by means of reciprocal projection of the piston rod 35a of the rack open cylinder 35 of the re-

spective frames projecting in the directions A and B in FIG. 10.

Also, the tools 37 stored in the tool pockets 31 of the respective tool rack 30 are developed on a plane SF formed by the surfaces of the tool racks 30 as shown in FIG. 10. Accordingly, the tool robot 10 is caused to move in the directions as shown by the arrows A and B parallel to the plane SF on which the tools 37 are developed. Furthermore, the hand mechanical portion 22 with the tool grasping portion 25 mounted thereon are caused to move in the directions as shown by the arrows I and J perpendicular to the moving direction of the main body 11 and parallel to the plane SF on which the tools 37 are developed.

In this way, when the tool robot 10 is brought to be in a correct position opposite to the tool rack 30 including the tool pocket 31 with the tool 37 to be fed stored therein, the piston rods 33a of two unlocking cylinders 33 mounted on the upper and lower portions of the tool robot main body 11 are caused to project in the direction as shown by the arrow D in FIG. 15. As a result, the front end of the piston rod 33a and the unlocking pin 32g of the connecting mechanism 32 of the tool rack 30 are abutted with respect to each other. Furthermore, the unlocking pin 32g is pushed in resisting the biasing force of the coil spring 32i in the direction as shown by the arrow D in FIG. 13. Due to the foregoing, the lock pin 32e is also moved in the direction of D through the pin 32f. As a result, the pin 32a of the tool rack 30D at the right side in FIG. 14 (the tool 37 to be fed is stored in this tool rack 30D), which was in a connected state with the lock pin 32e through the connecting groove 32b is canceled the connected state with the lock pin 32e and brought to be in such a state as ready to escape from the connecting hole 32e.

Then, the rack opening cylinder 35 mounted on a frame corresponding either to the main frame 2 or the sub-frame 3 with the tool rack 30, for which the unlock pin 32g is pressed, is driven. As a result, the piston rod 35a is caused to project in the direction as shown by the arrow B in FIG. 10. When the piston rod 35a is projected in the direction as shown by the arrow B, the tool rack 30A fixed to the piston rod 35a and at least one tool rack 30 which is in the connected state with the tool rack 30A through the connecting mechanism 32 starts moving in the direction B (of course, it is feasible that only the tool rack 30A is moved in the direction B depending on circumstances). The tool racks 30 are moved in the direction B in such a manner as that the pin 32a is separated from the engaging hole 32c by serving the tool rack 30 provided with the unlocking pin 32g abutted with the unlocking cylinder 33 and the tool rack 30D at the right side in FIG. 14 which was in the connected state with the tool rack 30 just mentioned through the engaging hole 32c as the boarder line. Among the tool racks 30 which started the movement, between the tool rack 30D at the left side in FIG. 14 and the next tool rack 30 to the left in FIG. 14, a space corresponding to the stroke ST of the rack opening cylinder 35 is formed. The tool racks 30A and 30D are coincide with each other in FIGS. 12 and 14. It is noted that this explanation is applicable whether they are coincide or not.

In this way, when all of the tool racks 30 at the right side than the tool rack 30D provided with the tool 37 to be fed in FIG. 1 are moved to the direction B by stroke ST from, the motor 19 of the tool robot 10 is driven to rotate the feed screw 21 for a suitable angular amount in

the normal and reverse directions through the timing belt 20 etc. As a result, the hand mechanical portion 22 engaged with the feed screw 21 is moved along on the main body 11 in the directions as shown by the arrows I and J through the guide rails 11a, 11a. At this time, the hand mechanical portion 22 moves through the space between the tool racks 30 and 30D opened by the rack opening cylinder 35 in the directions I and J. Thus, the hand mechanical portion 22 does not interfere with the tools stored in the tool rack 30. Then, the tool grasping portion 25 provided at the hand mechanical portion 22 is brought to be in alignment with the vertical position of the tool pocket 31 with the tool 37 to be fed stored therein. In this state, the cylinder 23 is driven to cause the piston rod 23a to project in the direction as shown by the arrow D in FIGS. 6 and 7 in such a manner as to slide two guide rods 25a, 25a of the tool grasping portion 25 with respect to the slide bearing 22a.

Consequently, as shown in FIG. 6, the tool grasping groove 25f of the tool grasping portion 25 and the tool 37 to be fed stored within the tool racks 30D are brought to be in alignment in phase with respect to the directions as shown by the arrows C and D, and also with respect to the vertical direction in FIG. 3.

Then, the motor 15 is rotated again for a predetermined amount to move the main body 11 together with the tool grasping portion 25 in the direction B. Due to the foregoing, the tool holder of the tools 37 is engaged in the tool grasping groove 25f. In this state, the cylinder 25c is fed with a pressure oil to press the arm 26 in the direction H around the pin 26a so that the tools 37 are firmly held within the tool grasping groove 25f. Since the arm 26 is normally energized by the coil spring 25e toward the side H, even if feed of the pressure oil to the cylinder 25c is suddenly stopped, the tool 37 will not come off from the tool grasping groove 25f. Also, since engagement of the tool 37 into the tool grasping groove 25f is performed in the state that the pressure oil is not fed to the cylinder 25c due to the movement of the tool grasping portion 25 in the direction B towards the tools 37 side, the arm 26 is, while rotating, brought to be engagement in the tool grasping groove 25f resisting the biasing force of the coil spring 25e by the tool holder of the tools 37. Thus, the grasping action with respect to the tool 37 is smoothly performed.

In this way, when the tool 37 is grasped by the tool grasping portion 25, the piston rod 23a of the cylinder 23 is retreated in the direction C. As a result, the tool 37 grasped by the tool grasping portion 25 is separated from the tool pocket 31 to move in the direction C together with the tool grasping portion 25 and then picked up.

When the tool grasping member 25 is moved in the direction C together with the tool 37, the motor 19 is driven to suitably move the hand mechanical portion 22 and the tool grasping portion 25 in the directions I and J in order to bring the tool 37 back to the tool robot travelling area ARA. At the same time, the tool 37 is brought to be in alignment with the vertical position of the intermediate feed pocket 36. Thereafter, the motor 15 is driven to move the main body 11 in the direction B in such a manner as to permit the hand mechanical portion 22 to pass through the tool robot travelling area ARA, so that the tool 37 in the grasped state is moved so far as to the tool rack 30B fixedly provided at the rightmost side of the main frame 2 passing through the main frame 2.

In the meantime, the rack opening cylinder 35 causes the piston rod 35a to retreat in the direction A. As a result, the plurality of tool racks 30 including the tool rack 30_A which were moved in the direction B till this time are brought back in the direction A. And, as shown in FIG. 14, the pin 32a of the tool rack 32_D from which the tool 37 was picked up is caused to engage in the engaging hole 32c of the tool rack 30 adjacent to the left to the tool rack 30_D which was separated and picked up the tool 37 therefrom as described. Due to the foregoing, the space so far formed is closed. And, a space corresponding to stroke ST of the rack opening cylinder 35 is formed between the tool rack 30_A and the tool rack 30_B at the rightmost side of the main frame 2 or the sub-frame 3. On the other hand, when the pin 32a is inserted in the engaging hole 32c, the pin 32a is brought to be engagement with the the lock pin 32e through the engaging groove 32b in such a manner as to forcedly move the lock pin 32e together with the pin 32f and the unlocking pin 32g in the direction as shown by the arrow D resisting the biasing force of the coil spring 32. The tool rack 30_D and the tool rack 30 left thereto in FIG. 14 separated till this time are connected through the pin 32a as in the initial state. Since the engagement between the engaging groove 32b and the pin 32e is made through their inclining surfaces 32j and 32k, the connection between the tool rack 30_D and its left side tool rack 30 is smoothly and surely made in such a manner as that both the racks 30 are intimately contacted with each other.

In this way, when all of the tool racks 30 excepting the tool racks 30_B are integrated with respect to the main frame 2 as well as the sub-frame 3 respectively, the tool robot 10 which was brought to be in a position opposite to the intermediate feed pocket 36 of the tool rack 30_B of the main frame 2 actuates the cylinder 23 to project the piston rod 23a in the direction D, so that the tool 37 grasped by the tool grasping portion 25 is inserted in the tool holding portion 36g of the intermediate feed pocket 36. At this time, all of the tool racks 30 excepting the tool racks 30_B are moved in the direction A in FIG. 1. Since a space corresponding to the stroke ST (or more) of the rack opening cylinder 35 is formed between the tool racks 30_B and 30_A, even if the tool grasping member 25 is projected toward the tool rack 30, i.e. in the direction D, the tool grasping member 25 and the tool rack 30 as well as the tool 37 in the tool rack 30 do not interfere with each other. Thus, the tool 37 can be inserted in the tool holding portion 36g smoothly.

When the tool 37 is inserted in the tool holding portion 36g, feed of the pressure oil to the cylinder 25c is broken. In the foregoing state, the main body 11 is moved in the direction A together with the tool grasping member 25. Then, the arm 26 of the tool grasping member 25 is pivoted in the direction G resisting the biasing force of the coil spring 25e, and disengaged from the tool 37. As a result, the tool 37 is held in the intermediate feed pocket 36 in such a manner as that the lock pin 36t energized in the direction I by the coil spring 36u is engaged in the groove portion 37b of the pull stud 37a as shown in FIG. 17.

By the way, the tool 37 stored in the intermediate feed pocket 36 is, thereafter, fed again to the machine tool such as a machining center etc. by ATC apparatus (ATC stands for automatic tool changer. Hereinafter referred to as "ATC apparatus") at the machine tool side and mounted on a spindle. While, a tool 37 which

was mounted on the spindle of the machine tool and completed in machining work is returned to the intermediate feed pocket 36 by the ATC apparatus. The feeding of the tools 37 to the intermediate feed pockets 36 in the tool storing and feeding apparatus 1 are, as shown in FIGS. 1 through 2, performed by grasping the tools 37, more precisely, the left portions of the tool holders 37c of the tools 37 in FIG. 1 which are stored in the respective tool racks 30. Generally, ACT apparatus at the machine tool side performs changing work of tools by grasping the right side portions thereof in FIG. 1 (that is, ATC apparatus at the machine tool side can physically occupy only the right side of the tool storing and feeding apparatus 1). Accordingly, if the tool holder 37c is symmetric in its shape with respect to the right and left parts thereof, no problem is involved. However, regarding special tools 37 held by an asymmetric tool holder 37c, there arises the inconvenience that if the tool grasping portion 25 grasps the graspable portion at the left side of the tool 37 (accordingly, the right side of the tool 37 is an ungraspable portion), the tools 37 inserted into the intermediate pockets 36 at the ATC apparatus side can not be grasped if left in the state as they are.

In view of the above, when the tool 37 is set in the intermediate feed pocket 36 by the tool robot 10, the cylinder 36q is driven so that the rod 36r is projected in the direction as shown by the arrow I in FIG. 17. As a result, as shown in FIG. 18, the rotary holder 36b is rotated by 180° through the pinion gear 36p and rack 36s formed on the rod 36r. Since the rotary holder 36b is, as shown in FIG. 16, provided with the key 36v for engaging in the key groove formed in the tool 37, the tool 37 is rotated by 180° in synchronism with rotation of the rotary holder 36b. On the other hand, when the rotary holder 36b is rotated by 180°, the rotation is transmitted to the shaft 36i through the gears 36l and 36k, which further causes the cleaning holder 36d to rotate in the same direction as that of the rotary holder 36b through the gears 36j and 36h. Then, the cleaning brush 36f mounted on the cleaning holder 36d is rotated together with the cleaning holder 36d to clean out foreign matters such as dust attached to a taper shaft 37d of the tool holder 37c, which is intimately contacted with the spindle of the machine tool for holding the tool 37 at the time when the tool 37 is mounted on the spindle. Thus, precise machining work can be obtained. The cleaning holder 36d is rotated for several times while the rotary holder 36b is rotated by 180° due to gear rate. Thus, the taper shaft 37d can be cleaned smoothly in its entire periphery. At the same time, since a compressed air is fed into the tool holding portion 36g through an air feed hole 36w formed in the right end of the frame 36a in FIG. 17 passing through the the rotary holder 36b, the foreign matters such as dust etc. removed by the cleaning brush 36f are discharged outside through a space 38 between the tool 37 and the rotary holder 36b. Thus, the taper shaft 37d is maintained in a clean atmosphere. In this way, when the tool 37 is rotated by 180° within the tool holding portion 36g while cleaning the taper shaft 37d, the graspable side of the tool 37 is brought to be at the grasping side, e.g. the right side in FIG. 1, by ATC apparatus of the machine tool. Thus, the tool 37 is smoothly fed to the machine tool thereafter by ATC apparatus.

On the other hand, regarding the tool 37 returned to the intermediate feed pocket 36 by ATC apparatus, the cylinder 36q is driven to move the rod 36r in the direc-

tion J in FIGS. 17 and 18. Then, the rotary holder 36b is rotated by 180° but in the opposite direction through the rack 36s and pinion gear 36p to bring the graspable side of the tool 37 from the right side in FIG. 1 to the left side that the tool robot 10 can grasp. At the same time, the taper shaft 37d of the tool 37 is cleaned by the cleaning brush 36f in the same manner as described. Thus, the taper shaft 37 is maintained in its clean state.

Subsequently, the cylinder 23 of the tool robot 10 is driven to project the piston rod 23a in the direction as shown by the arrow D in FIGS. 6 and 7. As a result, while the distance between the tool rack 30_A and 30_B in its opened state is maintained ST (or more), the tool grasping portion 25 is entered therein without interfering with the tool rack 30_A etc. as described, and brought to be in a position where the tool grasping groove 25f and the tool holder 37c of the tool 37 returned by ATC apparatus within the intermediate feed pocket 36 are in alignment in phases in the directions as shown by the arrows C and D, as well as in the vertical direction in FIG. 3. When the motor 15 is rotated for a predetermined amount to move the main body 11 in the direction B together with the tool grasping portion 25, the tool holder 37c of the tool 37 is brought to be engaged in the tool grasping groove 25f. In this state, the pressure oil is fed to the cylinder 25c to press the arm 26 in the direction H around the pin 26a in order to firmly support the tool 37 in the tool grasping groove 25f in order not to drop off.

In this way, when the tool 37 is grasped by the tool grasping member 25, the piston rod 23a of the cylinder 23 is retreated in the direction C. As a result, the tool 37 held by the tool grasping member 25 is separated from the intermediate feed pocket 36 and moved in the direction C together with the tool grasping member 25 and picked up.

At the time when the tool grasping member 25 is moved in the direction C together with the tool 37, the motor 15 is driven to move the main body 11 in the direction A in such a manner as that the hand mechanical portion 22 is travelled within the tool robot travelling area ARA in order to feed the tool 37 in the grasped state so far as to the tool rack 30 in which the tool 37 is to be stored.

In this way, when the tool robot 10 is correctly brought to be in a position opposite to the tool rack 30 including the tool pocket 31 in which the tool 37 is to be stored, the piston rods 33a of two unlocking cylinders 33 provided at upper and lower portions of the tool robot main body 11 are projected in the direction as shown by the arrow D in FIG. 15. Then, the front end of the piston rod 33a and the unlocking pin 32g of the connecting mechanism 32 of the tool rack 30 are brought to be in abutment with respect to each other, and the unlocking pin 32g is further pushed in in the direction as shown by the arrow D in FIG. 13 resisting the biasing force of the coil spring 32i. Due to the foregoing, the lock pin 32c is also moved in the direction D through the pin 32f. As a result, the pins 32a of the adjacent tool rack 30_D (this tool rack 30_D has the tool pocket 31 in which the tool 37 to be returned is stored) which were in the engaged state through the the lock pin 32e and the engaging groove 32b, are disengaged from the lock pin 32e, and ready to be escaped from the engaging hole 32c in which the pin 32a was engaged.

As a result, the rack opening cylinder 35 is mounted on the frame corresponding either to the main frame 2 or the sub-frame 3 on which the tool rack 30 pressed

with the unlocking pin 32g is mounted is driven to project the piston rod 35a in the direction as shown by the arrow B in FIG. 10. When the piston rod 35a is projected in the direction as shown by the arrow B, the tool rack 30_A fixed to the piston rod 35a, as well as at least one tool rack 30 which is in the connected state with the tool rack 30_A through the connecting mechanism 32 start moving in the direction B. The tool racks 30 are moved in the direction B in such a manner as that the pin 32a is separated from the engaging hole 32c, serving the tool rack 30 provided with the unlocking pin 32g abutted with the unlocking cylinder 33 and the right side tool rack 30_D in FIG. 14 which was in engagement with the tool rack 30 through the engaging hole 30c as the boarder line. As a result, a space corresponding to the stroke ST of the rack opening cylinder 35 is formed between the tool rack 30_D and the tool rack 30 at the left side thereto in FIG. 14.

In this way, at the time when all of the tool racks 30 at the right side in FIG. 1 than the tool rack 30_D provided with the tool pocket 31 to which the tool 37 is to return are moved by the stroke ST in the direction B, the motor 19 is driven to suitably move the hand mechanical portion 22 and the tool grasping portion 25 in the directions I and J in order to bring the tool 37 of the tool grasping portion 25 to be in a correct position corresponding to the tool pocket 31 of the tool rack 30_D to which the tool 37 is to be returned. Subsequently, the main body 11 is moved for a predetermined amount in the direction B, so that the tool 37 of the tool grasping portion 25 and the tool pocket 31 of the tool rack 30_D to which the tool 37 is to be returned are brought to be opposite with respect to each other.

Subsequently, the cylinder 23 is driven to project the piston rod 23a in the direction as shown by the arrow D in FIGS. 6 and 7. As a result, the tool grasping portion 25 is caused to engage in the space between the tool racks 30 and 30_D opened by the rack opening cylinder 35 without interfering with the tool rack 30 etc, so that the tool 37 grasped is inserted in the predetermined tool pocket 31 in the tool rack 30_D.

When the tool 37 is inserted in the tool pocket 31, feed of the pressure oil is broken. In the foregoing state, the main body 11 is moved in the direction A together with the tool grasping portion 25. As a result, the arm 26 of the tool grasping portion 25 is brought to be disengaged from the tool 37 while pivoting in the direction G resisting the biasing force of the coil spring 25e. As a result, the tool 37 is held in the tool pocket 31.

In the foregoing state, the tool grasping portion 25 is returned in the direction C. At the same time, the tool grasping portion 25 is suitably moved in the directions I and J to return to the tool robot travelling area ARA.

As a result, the rack opening cylinder 35 is driven in the direction A in order to integrate again the tool racks 30 which were in a separated state for returning the tool 37 through the connecting mechanism 32. In this way, the returning action by the tool robot 10 is completed. The tool robot 10 is prepared for the next feeding action of the tool 37.

Nextly, setting of the tool 37 with respect to the present tool storing and feeding apparatus will be described.

Among the tool racks 30 mounted on the sub-frame 3 of the tool storing and feeding apparatus 1, the tool pocket 31_A third from the bottom of the tool rack 30 at the left side in FIG. 1 is used as a station for attaching and detaching the tools 37. When a worker sets the tools

37 in the tool pockets 31 and collects the tools 37 after used from the respective tool pockets 31 of the respective tool racks 30 of the tool storing and feeding apparatus 1, such operation is performed through these tool pockets 31_A. That is, when the tool 37 is to be set in the tool pocket 31 of the respective tool racks 30, the tool 37 to be set is set in the tool pocket 31_A by hand or through a tool feeding means such as a tool feeding robot etc. In the foregoing state, the tool robot 10 is driven to cause the robot 10 to grasp the tool 37 set in the tool pocket 31_A. At the same time, the tool 37 is delivered so far as to the tool pocket 31 in which the tool 37 is to be stored and stored therein as in the same manner when the tools 37 are stored in the respective tool pockets 31 from the intermediate feed pocket 36. In this way, the tools 37 to be stored are set in the tool pocket 31_A one after another. By storing in the respective tool pockets 31 by the tool robot 10, the tools 37 are set to the tool storing and feeding apparatus 1. The foregoing is also applicable to the case where the tools 37 already set are collected from the respective tool pockets 31. That is, the tools 37 to be collected from the respective tool pockets 31 are delivered by tool robot 10 so far as to the tool pocket 31_A serving as the tool attaching and detaching station and mounted therein. The tools 37 are detached and collected by a worker, etc. therefrom. In this way, by using the predetermined tool pocket 31_A as the tool attaching detaching station, the tools 37 can be set to a desired place in the tool storing and feeding apparatus 1 by merely attaching into the tool pocket 31_A by a worker, etc. Similarly, the collecting of the tools 37 from the tool storing and feeding apparatus 1 can be performed at one place in the tool pocket 31_A. Thus, much convenience is obtained. Provision of the tool attaching and detaching station is not limited to one place of the tool pocket 31_A. Instead, it is of course possible to use a plurality of tool pockets 31 as the tool attaching and detaching station.

Also, as in the present embodiment, if a part of tool racks 30_B are fixedly provided in such a manner as to be independent of the group of tool racks 30 which are moved and opened by means for moving the tool racks 30 such as the rack opening cylinder 35 etc., regarding the tools 37 set to the fixed tool racks 30_B, the tools 37 can be immediately attached and detached by the tool robot 10 without opening the tool racks 30. Accordingly, as for tools 37 which are frequently used, or in the case machining time is so short that if the tools are to be selected by usual opening and shutting action of the tool racks 30, time for feeding the tools 37 by the tool robot 10 to the machine tool becomes longer than the machining time, such tools 37 may be attached to the fixed tool racks 30_B, so that time required for opening and shutting the tool racks 30 can be saved. Thus, case-by-case prompt feeding of the tools 37 can be obtained.

Furthermore, the tool storing and feeding apparatus 1 according to the present embodiment comprises two frames, namely, one piece of the main frame 2 and one piece of the sub-frame 3. Since the main frame 2 and the sub-frame 3 are of module constitution as shown in FIGS. 1 and 2 which can be freely separated and connected, the frames can be suitably combined depending on numbers of the tools 37 to be fed, for example, only main frame 2, a main frame 2 and a sub-frame 3, and a main frame 2 and a plurality of sub-frames 3. That is, since the main frame 2 and the sub-frame 3 are extendably and connectably provided with travelling guide means such as the guide rails 6, 9 and the rack 7 etc. for

the tool robot 10 to travel in the travelling direction of the tool robot 10, the number of the sub-frame 3 can be increased with respect to the main frame 2 according to necessity. Furthermore, if the travelling guide means is connected in such a manner as to penetrate through both the frames, the travelling of the tool robot 10 between both the frames is immediately made possible. Thus, the tools to be fed can be easily increased in number.

In the above embodiment, description is made on the case where the tools 37 are developed, as shown in FIG. 11, on a vertical plane SF. However, the tool robot 10 according to the present invention is of course applicable irrespective of the direction of the developing plane of the tools 37. It is of course applicable even if the tools 37 are developed in the horizontal direction.

In the above embodiment, description is made on the case wherein there is provided the intermediate feed pocket 36, in which the predetermined tool 37 is set after picked out from the tool rack 30 by means for delivering and feeding tools such as a tool robot 10, and the tool 37 set in the intermediate feed pocket 36 is fed and mounted on the spindle of the machine tool by ATC apparatus provided at the machine tool side. However, instead of providing the intermediate feed pocket 36, means for delivering and feeding tools may of course directly deliver the tool 37 so far as the spindle of the machine tool and mount the same thereon.

As described in the foregoing, according to the present invention, it includes a movable plurality of tool racks in the shape of a band plate, the tool racks 30 being provided with a plurality of tool pockets 31 for storing tools 37 arranged in the longitudinal direction thereof, an intermediate feed pocket 36 for delivering the tools 37, and means for delivering and feeding the tools 37 such as the tool robot 10 etc. adapted to deliver and feed the tools 37 between the tool rack 30 and the intermediate feed pocket 36. Accordingly, the tools 37 can not only be stored in the tool rack 30 in high density, but also when the tools 37 are delivered by the delivery and feed means, the delivery and feed means and the tools 37 etc. adjacent to the delivery and feed means are prevented from interfering with each other since the tool racks 30 are movable, thereby unnecessary the provision of a predetermined distance for avoiding interference between the tool racks 30. Accordingly, the tool racks 30 can be arranged side by side in a continuous manner. Thus, even several hundreds of tools 37 can be easily stored in a limited space.

Furthermore, since a number of tools 37 can be stored in compact, the feeding of the tools 37 between the tool racks 30 and the intermediate delivery pocket 36 can be performed in a short time by the delivery and feed means. Thus, prompt feeding of the tools 37 to the machine tool is obtained.

Also, in the case the tool racks 30 are provided with a tool robot travelling ARA, where the tool pockets 31 are not provided, transversing the entirety of the respective tool racks 30, and means for delivering and feeding the tools 37 are movably provided through the travelling area ARA, the tools 37 to be fed by the delivery and feed means can be moved within the travelling area ARA without interfering with tools 37 stored in other tool racks 30. Besides, since the delivery and feed means can be disposed near to the tool racks 30 side, due to provision of the travelling area ARA without considering interference with the tools 37 stored in the tool racks 30, the tool storing apparatus 1 can be made very

small in its width in the directions as shown by the arrows C and D in FIG. 5. Thus, the entirety of the storing apparatus 1 can be made small.

Also, due to the provision of the intermediate feed pocket 36 in a position corresponding to the travelling area ARA of the delivery and feed means, the means for delivering and feeding the tools 37 which deliver the tools 37 between the respective tool racks 30 and the intermediate feed pocket 36 through the travelling area ARA is not required to determine its position with respect to the longitudinal direction of the tool racks 30, i.e., the direction as shown by the arrows I and J in delivering the tools 37 for the intermediate feed pocket 36. Thus, time required for feeding the tools 37 to the machine tool can be shortened to that extent, and effective feeding operation of the tools 37 can be obtained.

Furthermore, in a tool storing and feeding apparatus 1 including frames such as a main frame 2 and a sub-frame 3, etc. provided with the means for storing the tools 37 such as a plurality of tool pockets 31 developed on a plane SF, the frames are provided with travel guide means such as the guide rails 6 and 9, the rack 7, etc. in parallel with the plane SF on which the tools 37 are developed, the travel guide means being movably provided with the main body 11 of the means for delivering and feeding the tools 37, the main body 11 being movably provided with the hand mechanical portion 22 vertical to the moving direction of the main body 11 and parallel to the plane SF, the hand mechanical portion 22 being provided with the tool grasping portion 25 which is reciprocally projectable with respect to the tool storing means. Accordingly, the tool grasping portion 25 can immediately move to a required position on the plane SF on which the tool storing means is developed in order to attach and detach the tools 37. Thus, effective handling and feeding of the tools can be obtained.

Also, since there are the provision of a plurality of tool racks 30 in the shape of a band plate, the tool racks 30 being provided with a plurality of tool pockets 31 for storing the tools 37 therein and arranged in the longitudinal direction of the tool racks 30, means for delivering and feeding the tools 37 such as the tool robot 10, the plurality of tool racks being arranged side by side in a continuous manner when in the normal storing state of the tools 37, the tool racks 30 being moved in such a manner as to separate the tool racks 30 serving the tool rack 30_D provided with the tool pocket which the tool is attached to or detached from as a boarder line, thereby forming a space between the tool rack 30_D and the tool rack 30 adjacent thereto at the time when the tool 37 is attached to and detached from a predetermined tool pocket 31, the tool 37 being attached to and detached from the tool pocket 31 by the delivery and feed means by using the space formed between the tool rack 30_D and the tool rack 30 adjacent thereto while avoiding occurrence of interference between the delivery and feed means, and the tool racks 30 and other tools 37. Accordingly, the tools 37 can be stored in the tool racks 30 in high density. Besides, at the time when the tools 37 are delivered by the deliver and feed means, interference between the delivery and feed means and the tools 37 etc. of the adjacent tool rack 30 can be prevented by movement of the tool racks 30. Therefore, it is no more required to fixedly provide a distance for avoiding interference between the tool racks 30 with respect to each other. Accordingly, the tools racks 30 can be arranged side by side in a continuous manner.

Thus, even several hundreds of tools 37 can be easily stored in a limited space.

Although the present invention has been described in its preferred form, the embodiment described in this specification is utilized for purposes of exemplifying the invention and not in limitation thereof. The scope of the invention is defined in the appended claims and is by no means limited in the description of the embodiment. Accordingly, it should be understood that all alternations and modifications which belong to the claims are considered to be within the scope of the present invention.

What is claimed is:

1. A tool storing and feeding apparatus comprising:
 - a frame defining a first plane having perpendicular longitudinal and latitudinal axes;
 - a plurality of tool racks located within said frame, each tool rack being longer along the longitudinal axis than along the latitudinal axis, said tool racks being mounted so as to be movable along the latitudinal axis and so as to define a predetermined space between two adjacent tool racks, each said tool rack having a plurality of longitudinally arranged tool pockets for storing tools therein, each tool having a tool holder associated therewith;
 - moving means, connected to said frame, for moving said tool racks within said frame;
 - an intermediate feed pocket, located within a tool rack, for temporarily holding a tool delivered thereto so that it is available for use by a machining apparatus; and
 - delivering and feeding means, connected to said frame and moveable in a second plane parallel to said first plane, for delivering and feeding tools to said intermediate pocket from said tool pockets, the delivering and feeding including the steps of gripping a tool by its tool holder while the tool is in its tool pocket, removing the tool from the tool pocket, and delivering and feeding the removed tool to said intermediate feed pocket.
2. A tool storing and feeding apparatus according to claim 1, wherein each tool rack has an area where there are no tool pockets, said areas thereby together forming an extended latitudinal and narrow longitudinal area along the outer surfaces of said tool racks such that said delivery and feed means can move freely in that portion of said second plane corresponding to said extended area and not interfere with the other tool racks or stored tools in the apparatus.
3. A tool storing and feeding apparatus according to claim 2 wherein said intermediate feed pocket is located adjacent to said extended area where there are no tool pockets.
4. A tool storing and feeding apparatus according to claim 3 wherein said delivery and feeding means includes means for removing a tool from said intermediate tool pocket and conveying it back to its original tool pocket by moving along that portion of said second plane corresponding to said extended area where there are no tool pockets, moving along said predetermined space so that the tool may be conveyed to its original pocket, and conveying the tool from said predetermined space back into its original tool pocket where it is again stored.
5. A tool storing and feeding apparatus according to claim 4 in which said delivery and feeding means includes means for grasping a tool which can extend from said delivery and feeding means and can remove or

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place a tool into a tool pocket or said intermediate feed pocket.

- 6. A tool storing and feeding apparatus comprising:
 - a frame defining a first plane having perpendicular longitudinal and latitudinal axes; 5
 - a plurality of tool racks included within said frame, each tool rack being longer along the longitudinal axis than along the latitudinal axis, said tool racks being mounted so as to be movable along the latitudinal axis and so as to define a predetermined space between two adjacent tool racks; 10
 - a plurality of tool pockets, included within said tool racks and longitudinally arranged therein, for storing therein tools, each tool having a tool holder associated therewith; 15
 - moving means, connected to said frame, for moving said tool racks latitudinally within said frame so that said predetermined space can be formed between two tool racks; 20
 - moveable body means, which can move in a second plane parallel to said first plane, for delivering and feeding tools, said moveable body means including a hand mechanical portion moveable within said space between two tool racks, and said hand mechanical portion including a tool grasping portion for grasping, from said space, a tool by the tool holder so that the tool may be removed from or returned to its tool pocket; and 25
 - travel guide means, attached to said frame and extending along the latitudinal direction thereof, for guiding the motion of said moveable body means. 30
- 7. A method of tool storing and feeding comprising:
 - arranging a plurality of tool racks relative to a plane having longitudinal and latitudinal perpendicular axes, each tool rack being longer along the longitu- 35

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- dinal axis than along the latitudinal axis, and said tool racks being mounted so as to be movable along the latitudinal axis;
- arranging a plurality of tool pockets for storing tools, with tool holders, in the longitudinal direction thereof within said tool racks;
- moving the tool racks in the latitudinal direction when a tool is to be removed from or replaced to its tool pocket, and separating from an adjacent tool rack the tool rack in which the tool pocket is located so that a space is formed between the tool rack in which said tool is to be removed from or replaced to and said adjacent tool rack;
- delivering and feeding tools with a delivering and feeding means to an intermediate feed pocket by: grasping tools from said space by the tool holders, thereby avoiding interference with the other tool racks and tools stored in the apparatus, removing the tools from their tool pockets, and, delivering and feeding the tools to the intermediate feed pocket so that the tools may be temporarily stored therein and used by a machine apparatus;
- returning the tools to their respective tool pockets from the intermediate feed pocket with the delivering and feed means by: grasping the tools by the tool holders, removing the tools from the intermediate feed pocket, and delivering and feeding tools back into their original tool pockets from said space, thereby avoiding interference between the delivering and feeding means and other tool racks and tools stored in the apparatus; and
- arranging said tool racks side by side in a continuous manner when the tools are stored.

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